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DESCRIPTION

Description

TECHNICAL FIELD

[0001] The invention relates to a method and an apparatus for processing and grading food articles according to claims 1 and 11 respectively, for example, based on at least one characteristic of the food articles, wherein the grading comprises arranging the food articles along a conveyor and/or grading the articles onto one or more receiving areas.

BACKGROUND

[0002] Conventional grading machines include arms and/or trays to grade food articles while the food articles move along a conveyor. Food articles are often graded based on different characteristics, such as weight. Such methods often require several human participants to double check automatic procedures performed by machines, or to perform additional actions not performed by machines.

[0003] For example, U.S. Patent 7,258,237 describes a grading technique that includes weighing and portioning an item. In the grading technique, natural foodstuff items with varying weights are subjected to a weighing-in, and are thereafter selectively fed together in a computer controlled manner. According to this reference, a robot device including a grip, operated by a control system, is used for removing items from a delivery station to a receiving area for placement into a particular batch.

[0004] Similar methods for poultry packaging are described in "Robotic Packaging of Poultry products, by K. Khodabandehloo, Department of Mechanical Engineering, University of Bristol ISBN 0442316615 (Routledge, 1992)" and "Benefits of Experts robots intelligence vs. Skill, by K. Khodabandehloo, Department of Mechanical Engineering, University of Bristol ISBN 0387537317 (Routledge, 1992)". The previous references disclose a robot used to place poultry portions into trays according to a defined scheme

[0005] Document WO 2016/139611 A2 discloses a method for grading a food article, the method utilizes a grading device to remove at least one of a plurality of portions of a food article from the surface of a grading conveyor, while transferring the remaining portions of the food article to a receiving conveyor.

DISCLOSURE

[0006] Applicants have discovered that one disadvantage of having a robot arm picking the articles up from a conveyor is that it is difficult to design a good gripper arm to handle (e.g., grasp) delicate food products that typically come in various sizes. If the gripper arm is big enough for the biggest articles, it will require significantly more space between small articles than would otherwise be needed. Furthermore, such gripping robotic arms are not able to grasp articles that are oriented very close to each other on the conveyor. For example, such gripping robotic arms would not be able to grasp fish portions that are cut prior to being graded, but wherein the cut portions are still in the shape of the original fillet, without disturbing or even damaging the surrounding portions.

[0007] Embodiments herein include methods for grading food articles on a surface, and/or robots and apparatus. The surface may be a conveyor having an in-feed end and an out-feed end. Some embodiments comprise cutting a food article (e.g., a fish fillet) into a plurality of portions that are bisected by a line that is parallel to the in-feed end and/or the out-feed end of the conveyor. In embodiments, each portion of a plurality of portions may have an alignment and orientation. Grading a portion of the plurality of portions may include moving at least one portion of the plurality of portions, while at least substantially maintaining the alignment and orientation of each portion of the plurality of portions. In particular examples, moving the at least one portion may remove the portion(s) from a surface whereupon the portions are disposed.

[0008] In some embodiments, a method for grading food articles includes cutting a food article into a plurality of portions oriented parallel to each other. Some examples include grading at least one of the plurality of portions that is oriented parallel to at least another of the plurality of portions, wherein the at least another of the plurality of portions is/are not graded. Some examples comprise grading at least one of the plurality of portions that is positioned on the conveyor such that each side of the at least one portion(s) is proximate a side of at least one adjacent portion; e.g., a cut portion is graded from within the middle of the shape of the original food article.

[0009] In some embodiments, a food article is cut into the plurality of portions, such that the cut portions are oriented very close to each other on the conveyor (for example, wherein the cut portions are separated by a space that is essentially the width of a blade of the cutting instrument). In some examples, at least one of the very closely oriented portions is graded without damaging and/or changing the orientation and/or alignment of the other portion(s) on the conveyor.

[0010] In particular embodiments, a method for grading food articles comprises at least one step selected from the group consisting of: capturing a first x-ray image of a food article; detecting at least a first portion of the food article to be removed, and at least a second portion of the food article to retain using the first x-ray image; cutting the first portion of the food article

away from the second portion of the food article; moving the first portion of the food article automatically with a machine; and capturing a second x-ray image of the second portion of the food article. Certain examples include a method comprising all of the foregoing steps.

[0011] In particular embodiments, a method for grading food articles comprises at least one step selected from the group consisting of: cutting a food article into a plurality of portions oriented parallel to each other, wherein each portion has an alignment and orientation; capturing an x-ray image of the plurality of portions oriented parallel to each other; and moving less than all of the plurality of portions automatically with a machine. Some examples comprise detecting which portions of the plurality of portions contain an undesirable component of the portion (for example, with a first x-ray machine); and moving only portions of the plurality of portions containing an undesirable component. In particular examples, the undesirable component is selected from the group consisting of bones (*i.e.*, a bone or bone fragment), cartilage, fat, defects in flesh, tough tissues, skin, blood, and organs. In certain examples, the undesirable component is a bone. In certain embodiments, at least one detected portion containing an undesirable component is moved automatically, and any remaining portion(s) comprising a further undesirable component are detected (for example, in a second x-ray machine).

[0012] Some embodiments include a grading device (*i.e.*, a robot), which grading device may have any number of degrees of freedom. In particular embodiments, the grading device may comprise a horizontally movable support member; a vertically movable support member slidably coupled to the horizontally movable support member; a first actuator attached to the horizontally movable support member; a second actuator attached to the vertically movable support member; and a means for moving at least one portion of a food article attached to the vertically movable support member (*e.g.*, a needle array, and a gripper). In some examples, the means for moving at least one portion of a food article may be utilized to move a plurality of portions at substantially the same time (*i.e.*, in one movement of the grading device).

[0013] Some embodiments include an automated food processing system that contains, in sequential order on a conveyor, a first x-ray machine, at least one cutting machine, and a second x-ray machine. In some embodiments, the cutting machine(s) is adapted to cut out a portion containing a bone or bone fragment from a food article, leaving one or more portions of the food article containing flesh. In some examples, the automated food processing system comprises computer programming to utilize information from the second x-ray machine to locate a bone or bone fragment in a food article portion, and a computer adapted to adjust the operation of the cutting machine(s) according to the location of a bone or bone fragment in a portion of a food article, so as to maximize the size of the one or more portions of the food article containing flesh that remain(s) after cutting. In particular examples, the automated food processing system comprises at least one grading device (*e.g.*, one, two, three, four, five, or more grading devices) that is adapted to move a portion of the food article containing bones after cutting, as determined by the second x-ray machine; for example, to reposition the portion on the conveyor before the cutting machine(s), or to remove the portion from the conveyor. The grading device(s) may be positioned anywhere in the automated food

processing system; for example, following an x-ray machine or conveyor.

[0014] In some embodiments, an automated food processing system comprises computer programming to utilize information from the first x-ray machine to locate a bone or bone fragment in a food article portion. In particular examples, the automated food processing system comprises at least one grading device that is adapted to move a portion of the food article containing bones after cutting, as determined by the first x-ray machine; for example, to reposition the portion on the conveyor before the cutting machine(s), or to remove the portion from the conveyor.

[0015] In some embodiments, the grading robot may include a first mounting member mounted to a side of a grading conveyor and a second mounting member mounted to a side of the grading conveyor (for example, a side other than that to which the first mounting member is mounted). The grading robot may include a first guide member horizontally mounted to both the first mounting member and the second mounting member, and a horizontally movable support member slidably coupled to the first guide member. The grading robot may include a second guide member mounted to the horizontally movable support member, and a vertically movable support member slidably coupled to the second guide member. The grading robot may in some examples comprise at least one additional actuator, so as to provide at least one additional degree of freedom. Furthermore, the grading robot may include a first actuator (e.g., air cylinder, motor, linear motor, traditional motor, and solenoid) attached at one end to the horizontally movable support member. The first actuator may be attached at another end to the second mounting member. The grading robot may include a second actuator attached at one end to the second guide member. The second actuator may be attached at another end to the vertically movable support member. In some examples, a grading robot may include at least one needle or gripper attached to the vertically movable support member.

[0016] Some embodiments include at least one realigning apparatus for aligning food article. In particular embodiments, a realigning apparatus for aligning a food article or portion of a food article may comprise a first mini-conveyor; a second mini-conveyor disposed proximate the first mini-conveyor; a first actuator attached to the first mini-conveyor; and a second actuator attached to the second mini-conveyor, wherein the first mini-conveyor is mounted with a hinge such that the first mini-conveyor is separable from the second mini-conveyor. In some embodiments, a realigning apparatus may include a first mini-conveyor disposed above a processing conveyor, and a second mini-conveyor disposed above the processing conveyor proximate the first mini conveyor. Both the first mini-conveyor and second mini-conveyor may be tilted at an angle, such that the first mini-conveyor and second mini-conveyor form a V-shape.

[0017] Some embodiments include a food processing apparatus. In particular embodiments, a food processing apparatus comprises at least one conveyor; at least one grading device (e.g., a robot); and at least one imaging system, at least one cutting machine, and/or at least one realigning apparatus. In particular embodiments, the food processing apparatus comprises at least one of: x-ray machine(s), manual quality check station(s), automated quality check

station(s), and realigning apparatus. Certain embodiments include a food processing apparatus comprising at least one conveyor; at least one x-ray machine; a first imaging system; at least one cutting machine; at least one quality check station; at least one additional imaging system; at least one grading device; at least one realigning apparatus; and at least one computer programmed to utilize information from the additional imaging system(s) to determine, for example, the location of a bone or bone fragment in a portion of a food article, the location of fat in a portion of a food article, the color of a portion of a food article, the location of a gap in a portion of a food article, the location of a visual defect in a portion of a food article, and the location of parasites in a portion of a food article, wherein the computer is programmed to utilize information about the movement of the at least one conveyor and any determined feature to adjust the position of the means for moving at least one portion of a food article of the grading device.

BRIEF DESCRIPTION OF THE DRAWINGS

[0018] The present disclosure may be understood more fully by reference to the following Detailed Description of several embodiments, which are illustrated in the appended figures, in which:

FIG. 1 includes a top view of an example of a food article **101** (*i.e.*, a fish fillet) cut into portions **117**, wherein included in the shape of the original food article **101** is a first plurality of portions **117** ("two," "three," and "four"), a second plurality of portions ("five," "six," "seven," and "eight"), and a third plurality of portions ("nine," "ten," and "eleven"), each of which is bisected by a line **114** parallel to out-feed end **115** of the conveyor upon which the article **101** is disposed. Referring to **FIG. 1**, portions **117** "three," "six," and "seven" are portions **117** that are positioned such that each side is proximate a side of at least one adjacent portion **117**. Referring again to **FIG. 1**, portions **117** "one" and "eight" are in series with portion **117** "three," and portions **117** "two" and "four" are parallel to portion **117** "three."

FIG. 2 includes a perspective view of an example of a food processing apparatus.

FIG. 3 includes a perspective view of an example of a 3D camera of an imaging system of a food processing apparatus.

FIG. 4(a-b) includes perspective views of illustrative cutting machines of a food processing apparatus. **FIG. 4a** includes a perspective view of an example of a "delta" or "spider" cutting robot (*i.e.*, a three degrees of freedom cutting robot). **FIG. 4b** includes a perspective view of an example of a four degrees of freedom cutting robot.

FIG. 5 includes a perspective view of an example of a robotic arm of a food processing apparatus.

FIG. 6a includes a perspective view of an example of a needle grading robot of a food processing apparatus. **FIG. 6b** includes a perspective view of a further example of a needle grading robot of a food processing apparatus. **FIG. 6(c-d)** include perspective views of a

representative means for moving at least one portion of a food article attached to a vertically movable support member. In this particular example, the means for moving at least one portion of a food article attached to a vertically movable support member is an example of a needle array attached to a lowermost portion of a vertically movable support member. In **FIG. 6c**, the needles of the array are positioned proximate the vertically movable support member. In **FIG. 6d**, the needles of the array are positioned distal the vertically movable support member.

FIG. 6e includes a perspective view of an example of a three degrees of freedom robot **677** that may be utilized in some embodiments, for example, as a spray-removal robot **651**. In particular embodiments, a three degrees of freedom robot **677** comprises a first primary axis **681** and a second primary axis **683** that can control the location of a parallel plate **679** in the Y and Z directions, and a third axis **685** that can tilt the parallel plate **679** in a plane that is perpendicular to the direction of the conveyor.

FIG. 7a includes a perspective view of a spray-removal grading section of a food processing apparatus **200**. In some embodiments, a spray-removal robot **651** in the spray-removal section uses a stream of fluid (e.g., water) to remove a cut food portion **117** from a conveyor system including a first conveyor **665**, for example, at an angle, as shown in **FIG. 7b**. **FIG. 7c** includes a perspective view of a spray-removal section of a food processing apparatus **200** that comprises a plurality of spray-removal robots **651** that forces at least one food portion **117** on the same area **669** of a first conveyor **665**, as shown in **FIG. 7d**, into the space between the first conveyor **665** and a receiving conveyor **667**.

FIGs. 8(a-b) include perspective views of elements of a spray-removal grading section of a food processing apparatus **200** that help illustrate means for the removal of a portion **117** that has already been cut from a fillet **101** by the operation of the spray-removal robot **651**.

FIG. 9a includes a perspective view of a two degrees of freedom grading robot of a food processing apparatus. **FIG. 9b** includes a view of the two degrees of freedom grading robot disposed to transfer at least one portion of the food article from a first conveyor to a second conveyor. In this example, the second conveyor is oriented in parallel with respect to the first conveyor. However, the second conveyor may alternatively be oriented perpendicularly, or at any other angle, with respect to the first conveyor. Furthermore, any grading robot (e.g., one, two, three, four, or more degrees of freedom grading robots described herein) may be utilized to transfer a portion of the food article from a first to a second conveyor. Referring again to **FIG. 9b**, in this illustration only one portion is transferred from a first to a second conveyor. However, any number of portions may be transferred, depending on the particular grading robot utilized. Conveyor belts may be positioned to keep the transfer between the belts as smooth as possible. Furthermore, a middle plate can potentially be included, and the second conveyor may in some examples be positioned a little bit lower than the first conveyor that originally comprises the portion(s) on its surface. **FIG. 9c** includes a perspective view of a further represented conveyor system. In this example, a second conveyor and a third conveyor are oriented to follow the first conveyor in its direction of movement. In this example, a grading robot may separate one or more portions of a food article from the remaining portions on the

surface of the first conveyor, such that the movement of the conveyor guides the separated portions onto the second conveyor, while guiding the remaining portions onto the third conveyor. **FIGs. 9(d-f)** include perspective views of a grading robot with a plate transferring portions of a food article from a first to a second conveyor. In **FIG. 9(d)**, the grading robot transfers portions from the first conveyor to a second conveyor oriented perpendicularly with respect to the first conveyor. In **FIG. 9(e)**, the grading robot transfers portions from the first conveyor to a second and a third conveyor that are oriented to follow the first conveyor in its direction of movement. **FIGs. 9(f-g)** include perspective views of a two degrees of freedom grading robot comprising a first, splitting plate in the direction perpendicular to the conveyor, and a second plate at the end of the first, splitting plate that can be rotated. **FIG. 9(f)** shows an example of rotation of the second plate being utilized to move portions of the food article from a first to a second conveyor. In this example, rotation of the plate moves a plurality of portions to a second conveyor oriented in parallel and on the right side with respect to the first conveyor. **FIG. 9(g)** shows an example of rotation of the second plate being utilized to move portions of the food article from a first to one of two further conveyors. In this example, rotation of the plate in one direction moves a plurality of portions to a second conveyor oriented in parallel and on the left side with respect to the first conveyor. In this example, rotation of the plate in the other direction would move the plurality of portions to a third conveyor oriented in parallel and on the right side with respect to the first conveyor. In some examples, a grading robot comprising a plate may have a further degree of freedom, such that the grading robot can lift diverting plate(s) from the conveyor. This functionality makes simplifies the task of cleaning the plates following use.

FIG. 9h includes a perspective view of a single degree of freedom grading robot, wherein the vertically movable support member is oriented at an angle with respect to the conveyor, so as to even further minimize the chance of damaging and/or changing the orientation and/or alignment of the other portions of the food article. For example, if the gripped portion(s) is to be moved then the chance of moving further portions is minimized by orienting the vertically movable support member at an angle, such that the gripped portion will be moved away from the further portions when it is moved from its original alignment and orientation on the conveyor.

FIGs. 9(i-k) include perspective views of a four degrees of freedom grading robot. **FIGs. 9(j-k)** specifically include perspective views of a four degrees of freedom grading robot comprising two means for moving at least one portion of a food article. In this example, the two means for moving at least one portion of a food article can rotate around an axis that is parallel to the conveyor plane. Referring to **FIGs. 9(i-j)**, a first means for moving at least one portion of a food article grips a portion of the food article (the pinbone portion of a fish fillet in the illustration of **FIG. 9(j)**). Referring to **FIG. 9k**, rotation of the vertically movable support member along the fourth degree of freedom moves the first means for moving at least one portion of a food article, with the gripped portion, away from the surface of the conveyor, while also moving a second means for moving at least one portion of a food article into position to grip a further portion.

FIG. 10(a-b) includes perspective views of illustrative realigning sections of a food processing

apparatus. **FIG. 10a** includes a perspective view of an example of a realigning section comprising realigning apparatus. **FIG. 10b** includes a perspective view of illustrative first and second realigning sections of a food processing apparatus.

FIG. 11 includes perspective views of a representative system that may be used to align food articles in some embodiments.

FIG. 11(a-c) shows a system including three conveyors. The conveyor furthest to the left is the first conveyor (e.g., an x-ray conveyor) in the conveyor's direction of movement. The second conveyor from the left may be a retractable infeed conveyor. The conveyor furthest to the right may also be a retractable infeed conveyor; for example, where a person stands to ensure that food articles are properly oriented, and/or would that there is a desired spacing between the food articles (e.g., from overlapping (less than 0 mm) to 100 mm, from adjacent (0 mm) to 100 mm, from about 10 mm to 100 mm, and about 10 mm). The outfeed end of the first conveyor and the infeed end of the second conveyor move together in the conveyor's direction of movement as shown with the blue arrow. There may be a product sensor (e.g., an imaging device) associated with the first conveyor that measures the distance between the food articles on the conveyor. For example, the product sensor may first measure the distance between consecutive food articles on the conveyor.

[0019] In the example shown in **FIG. 11(a)**, the spacing between food article A and food article B is higher (e.g., more than 100 mm) than the desired spacing (e.g., about 10 mm). In this case, the system will wait until food article A has reached the second conveyor, and then it will move the outfeed end of the first conveyor and the infeed end of the second conveyor at the same time, until the spacing between food article A and food article B is close to the desired spacing (e.g., approximately or exactly the desired spacing).

[0020] In the example shown in **FIG. 11(b)**, the desired spacing has been obtained between food article A and food article B. Once a sufficient part of food article B has been transferred over to the second conveyor, the outfeed end of the first conveyor (and the infeed end of the second conveyor at the same time) is moved back in the direction opposite to which the conveyor system is moving, such that it will be ready to move forward again for the next food article.

[0021] In the example shown in **FIG. 11(c)**, the desired spacing has been obtained between all three food articles.

[0022] Disclosed generally herein are food processing systems and apparatus comprising one or more of: at least one x-ray machine to determine the location of undesirable components (e.g., bones) within a food article (e.g., a fish fillet); at least one cutting machine to cut a food article into portions; at least one food grading apparatus for grading portions of a food article based on different characteristics; and at least one realigning apparatus, as well as methods utilizing the same. The grading apparatus may be able to grade portions of a food article

oriented parallel to each other and in series with each other with respect to the direction of movement of a conveyor surface, as is described in further detail below, and may be able to grade portions of a cut food article from the middle of the article. The grading apparatus may be able to grade portions while maintaining an original alignment and orientation of the portions.

[0023] The illustrations presented herein are not meant to be actual views of any particular food processing apparatus, x-ray machine, cutting machine, food grading apparatus, realigning apparatus, or component thereof, but are merely simplified schematic representations employed to describe illustrative embodiments. The drawings are not necessarily to scale.

[0024] Relational Terms: As used herein, any relational term, such as "first," "second," "over," "beneath," "top," "bottom," "underlying," "up," "down," etc., is used for clarity and convenience in understanding the disclosure and accompanying drawings, and does not connote or depend on any specific preference, orientation, or order, except where the context clearly indicates otherwise. The terms "vertical" and "horizontal" merely refer to a drawing figure as oriented on the drawing sheet, and in no way are limiting of orientation of a food processing apparatus, food grading apparatus, or any portion thereof.

[0025] Alignment: As used herein, the term "alignment" refers to the position of a food article and the surface of a conveyor in the vertical dimension; for example, the completeness of the contact between a food article and a conveyor surface. In particular examples, a food article may be flat, bunched, or folded. In some embodiments, whether the alignment of a food article portion during grading is "substantially preserved" may be determined by whether the food article portion(s) remains flat on the surface of the conveyor throughout the process; e.g., the entire bottom surface of the portion retains contact throughout the process with the surface of the conveyor.

[0026] Cutting: As used herein, the term "cutting" includes, for example and without limitation: cutting and removing unwanted components (e.g., bones, cartilage, fat, defects in flesh, tough tissues, skin, blood, and organs) from a food article, such as a fish fillet, and/or cutting a food article into portions. The term "advanced cut" refers specifically to the process by which a food article is cut into portions by a cutting machine.

[0027] Grading: As used herein, the term "grading" refers to a process by which portions of a food article (e.g., a fish fillet, cut so as to maintain the resulting portions together in the general shape of the original fillet; **FIG. 1**) are separated, for example, according to one or more selection criteria. In some embodiments, a food article is graded by a method comprising "movement" of at least one portion of the food article to an area that is separate from an area including at least one of the remaining portions of the food article. In some examples, a food article is graded by moving at least one portion of the food article to remove the portion(s) from a conveyor surface.

[0028] In series: As used herein, the term "in series" refers to portions arranged next to each

other in a direction in which a conveyor is moving. In the illustrative cut food article **101** of **FIG. 1**, portions "one," "two," "five," and "nine" are in series; *i.e.*, they are next to each other in the direction **119** the conveyor is moving.

[0029] Orientation: As used herein, the term "orientation" refers to the position of a food article and the surface of a conveyor in the two dimensions of the surface. In some embodiments, whether the orientation of food article portions during grading is "substantially preserved" may be determined by whether the position of one side (or edge) of the food article portion(s) is maintained throughout the process with respect to an edge of the conveyor. In some examples, "substantial preservation" of the orientation of food article portions may be determined by whether the general shape of the portion(s) is maintained throughout the process on the conveyor. For example, a bilaterally symmetrical portion may be flipped upside-down on the conveyor in these examples, wherein the orientation is substantially preserved, because the general shape of the portion is maintained.

[0030] Parallel: As used herein, the term "parallel" refers to portions arranged next to each other in a direction perpendicular to the direction in which a conveyor is moving. In the illustrative cut food article **101** of **FIG. 1**, portions "two," "three," and "four" are parallel; *i.e.*, they are next to each other in the direction perpendicular to the direction **119** the conveyor is moving.

[0031] Properly (aligned and/or oriented): As used herein, the term "properly aligned" refers to a food article or portion(s) thereof that is flat against a conveyor (*e.g.*, without any folds) upon which the article or portion(s) is being transported, and the terms "proper orientation," "oriented properly," and "properly oriented" mean that the food article or portion(s) thereof is positioned correctly with respect to the conveyor. In other words, the terms "proper orientation and alignment," "oriented and aligned properly," and "properly oriented and aligned" mean that the shape of a food article or portion(s) thereof is positioned in a certain manner with respect to the conveyor and the direction the conveyor is moving.

[0032] Robot: As used herein, the terms "robot" and "device" are used interchangeably.

[0033] Tray: As used herein, the term "tray" refers to any receptacle for a graded portion of a food article.

[0034] **FIG. 2** is a top perspective view of a food processing apparatus **200** according to some embodiments. The food processing apparatus **200** may detect and cut undesired portions **117** from food articles, for example, being carried through the food processing apparatus **200** by the directional movement of a feed conveyor **208** surface. The food processing apparatus **200** may grade food articles according to certain characteristics (*e.g.*, weight, quality, size, type, etc.). For example, the food processing apparatus **200** may be configured to automatically cut pin bones, other bones or bone fragments, cartilage, and/or other undesirable components from a food article **101**. The food processing apparatus **200** may cut the food article **101** into desired portions, **117** and grade the portions **117** according to at least one characteristic. In the

drawings, the food articles are illustrated by way of example as fish fillets; however, the food processing apparatus 200 in other examples is used to process and grade any of several different food articles (e.g., beef, pork, poultry, lamb, crustaceans, etc.).

[0035] The food processing apparatus 200 may be utilized in the meat industry to cut ribs away from a carcass, such that the ribs are not cut, but the food processing apparatus 200 can cut through other bones in the meat sections. The food processing apparatus 200 may be utilized in the poultry industry for fully automatic detection and cutting of cartilage, for example, in the front tip of chicken breasts, which commonly remain attached to the breasts after filleting.

[0036] An exemplary food processing apparatus 200 according to some embodiments may include one or more of each of: a feed conveyor 208; an aligning section 210; a first x-ray machine 212, 217; a cutting conveyor 214; a cutting machine 216; a first imaging system 234; a removal or check section 244, 254; at least a second imaging system 235; and at least one computer.

[0037] As shown in FIG. 2, an exemplary food processing apparatus 200 according to some embodiments may include a feed conveyor 208; an aligning section 210; a first x-ray machine 212; a cutting conveyor 214; a cutting machine 216; a first imaging system 234; an automatic removal section 244; a (e.g., manual) check section 254; at least a second x-ray machine 217; at least a second imaging system 235; a rejection section 220; a grading conveyor 218; at least one grading robot 224; at least one processing conveyor 226; at least one realigning section 800; at least one realigning apparatus 802; and at least one computer. With regard to each of the foregoing components of a food processing apparatus 200 according to certain embodiments, the computers described independently for each may in some examples be either a single central computer or in other examples a plurality of computers.

[0038] As shown in FIG. 2, a pre-trimming line 206 may precede the food processing apparatus 200. On the pre-trimming line 206, fish fillets 101 may be manually or automatically trimmed prior to entering the food processing apparatus 200. For example, on the pre-trimming line 206, undesirable components, for example, loose bones, cartilage, parasites, blood spots, or obvious defects in flesh, may be removed from fish fillets 101. In some embodiments, fish fillets 101 within the pre-trimming line 206 may include skin. In some embodiments, the fish fillets 101 may not include skin.

[0039] The feed conveyor 208 may follow the pre-trimming line 206, and may transport fish fillets 101 leaving the pre-trimming line 206 to the aligning section 210. In the aligning section 210, fish fillets 101 may be properly aligned and placed in a proper orientation prior to continuing through the food processing apparatus 200. For example, a fish fillet 101 may be properly oriented when a longitudinal length of the fish fillet 101 is substantially parallel to a length of a conveyor. As another non-limiting example, a fish fillet 101 may be properly oriented on a conveyor when a tail portion of the fish fillet 101 is positioned to come first as the fish fillet 101 is transported on the conveyor.

[0040] In some embodiments, alignment and orientation of fish fillets **101** may be performed manually. In some embodiments, the fish fillets **101** may be aligned and oriented automatically by an imaging device and automated robotic arm combination (e.g., a robotic arm may be utilized to rotate or push forward a food article, such as a fish fillet). Accordingly, each fish fillet **101** may be properly aligned and oriented prior to being fed into the first x-ray machine **212**. For example, **FIG. 11** shows a system that may be used to align food articles in some embodiments.

[0041] Fish fillets **101** may be fed one by one into the first x-ray machine **212**, which may capture a first x-ray image of each fish fillet **101**. The first x-ray machine **212** may also capture the precise location of bones within each fish fillet **101**. Additionally, the first x-ray machine **212** may capture the precise location of each fish fillet **101** with respect to the feed conveyor **208**. For example, the food processing apparatus **200** may include the x-ray machine described in U.S. Patent Application Publication No. 2012/0307013 A1, the disclosure of which is incorporated in its entirety herein by this reference. The first x-ray machine **212** may transfer information regarding the location of the bones within each fish fillet **101**, and the location of each fish fillet **101** with respect to the feed conveyor **208** to a computer. The feed conveyor **208** may convey the fish fillets **101** through the first x-ray machine **212**, and then off of the feed conveyor **208** and onto the cutting conveyor **214**. In some embodiments, the feed conveyor **208** and/or the cutting conveyor **214** may comprise one or more of a belt, cords, a plurality of members linked together, etc. The cutting conveyor **214** may feed the fish fillets **101** to be cut in the cutting machine **216**.

[0042] The computer may be programmed to track the movement of each fish fillet **101** as the fish fillet **101** moves through the food processing apparatus **200**. The computer may use images taken from the first x-ray machine **212**, in addition to information related to the movement of the feed conveyor **208** and cutting conveyor **214**, to determine an estimated location of each fish fillet **101** within the food processing apparatus **200**. However, some uncertainty may arise as to the precise location of each fish fillet **101** within the food processing apparatus **200**, for example, when the fish fillet **101** moves from the feed conveyor **208** to the cutting conveyor **214**. In some examples, the uncertainty is acceptable to the process. In other examples, this uncertainty is unacceptable to the process and more accuracy is needed. Therefore, particular examples may include an imaging system **234** on the cutting conveyor **214**. The imaging system **234** may capture a three-dimensional ("3D") image of each fish fillet **101**. In some examples, the imaging system **234** captures a 3D image of the fish fillet **101** as the fish fillet **101** is disposed on the cutting conveyor **214**, before the fish fillet **101** is subject to any further manipulations that may alter its alignment and/or orientation.

[0043] As shown in **FIG. 3**, the imaging system **234**, which may point towards the cutting conveyor **214**, in some embodiments may include a 3D camera **302**. The imaging system **234** may include a laser **304** that puts a light on the fish fillet **101**. In some embodiments, the imaging system **234** may capture a silhouette image or a full color 3D image. In some embodiments, the x-ray image of each fish fillet **101** may be used to generate a 3D image of

the fish fillet **101**. In some examples, the intensity of each pixel in the first x-ray image may be based on the thickness of the fish fillet **101**. For example, the thinner the fish fillet **101** is, the higher the intensity of a correlating pixel may be, and conversely, the thicker the fish fillet **101** is, the lower the intensity of a correlating pixel may be. With the 3D camera **302**, it may be possible to capture a height profile of the fish fillet **101** along the image.

[0044] The 3D image of each fish fillet **101** captured by the imaging system **234** may provide an accurate measurement of a volume of each fish fillet **101**. Furthermore, a color 3D image may provide information as to a location of fat within the fish fillet **101**. The 3D image may also provide more accurate information as to the weight distribution of each fish fillet **101**. For example, the imaging system **234** may transfer the 3D image to the computer. The computer may be programmed to determine an alignment and orientation of each fish fillet **101**. From any and all of the foregoing information, the computer may adjust cutting procedures (described in further detail below), for example, to account for the particular alignment and orientation of the fish fillet **101**.

[0045] The computer may match the first x-ray image of each fish fillet **101** captured by the first x-ray machine **212** with the 3D image of each fish fillet **101** captured by the imaging system **234** (e.g., by mapping the image from tail to head) to determine the precise location of the bones within each fish fillet **101** with respect to the cutting conveyor **214**. In some embodiments, this may be accomplished by matching a center of gravity of the first x-ray image and the 3D image of each fish fillet **101**, as well as the principle axis of the first x-ray image and the 3D image of each fish fillet **101**, as described in a mapping procedure of U.S. Patent Application Publication No. 2012/0307013 A1. In some embodiments, multiple x-ray images may be taken of each fish fillet **101** at differing angles, and the multiple resulting x-ray images are matched using a coordinate system, as described in U.S. Patent Application Publication No. 2012/0307013 A1. Any combination of the above described methods for determining the precise location of bones within a fish fillet **101** may be used. Furthermore, any of the mapping procedures described in U.S. Patent Application Publication No. 2012/0307013 A1 may be used.

[0046] The computer may determine an individualized cutting pattern for each fish fillet **101** using information related to the precise location of bones within each fish fillet **101**. For example, the cutting pattern of each fish fillet **101** may be determined to cut out portions **117** of the fish fillets **101** containing bones, while minimizing an amount of flesh removed with the bones. Furthermore, the cutting pattern may also be determined based on the weight distribution of the fish fillet **101** determined by the first x-ray image and 3D image. Thus, the cutting pattern can be determined to cut the fish fillets **101** into portions **117** of fixed weight, length, and/or in a pattern which optimizes a portion **117** yield. The cutting pattern for each fish fillet **101** may be superimposed onto the first x-ray image of the fish fillet **101**, 3D image of the fish fillet **101**, or both. The fish fillet **101** may then be cut into portions **117** according any of the methods and using any of the cutting machinery described in U.S. Patent Application Publication No. 2012/0307013 A1. The cutting machine **216** may include at least one cutting robot **400**, which is described in further detail below with reference to **FIG. 4**. In some

examples, a single cut portion **117** of a fish fillet **101** may contain all the parts of the fish fillet **101** having bones, and another cut portion **117** may include all the parts not having bones. A fish fillet **101** may be cut into a shape that maintains the outline of the original fish fillet **101**, wherein the shape comprises both portions **117** that are in series with one another, and into portions **117** that are parallel to each other.

[0047] FIG. 4 depicts two illustrative cutting robots **400**. However, any cutting robot (for example, any of the cutting robots described in U.S. Patent Application Publication No. 2012/0307013 A1) may be used in certain embodiments. The cutting robot **400** may be powered by any means known in the art, for example and without limitation, air cylinders, motors, and hydraulic powering means. The cutting robot **400** may also use any type of cutting known in the art, for example and without limitation, waterjet cutting, cutting with rotating knives, and ultrasonic cutting. If water jet cutting is used any type of cutting head can be used to focus the high pressure water into a thin beam that can cut through the food objects. The cutting robot **400** may also have any number of degrees of freedom. For example, a cutting robot **400** with a single degree of freedom may move in a direction perpendicular to the cutting conveyor **214**, or at an angle to the cutting conveyor **214**, such that it is capable of make straight cuts across the surface of the cutting conveyor **214**.

[0048] FIG. 4a illustrates a "delta" or "spider" cutting robot **401** with three degrees of freedom. If the x-axis is in the direction of movement of the cutting conveyor **214**, the y-axis is horizontal to the direction of movement of the cutting conveyor **214**, and the z-axis is the height from the cutting conveyor **214**, the "delta" or "spider" cutting robot **401** may be mounted with a base plate **402** in a plane parallel to the surface of the cutting conveyor **214**, and at a distance above the surface of the cutting conveyor **214**. The "delta" or "spider" cutting robot **401** may further include a parallel plate **404** that is parallel to the base plate **402**, where a cutting head (not shown) may be mounted. The "delta" or "spider" cutting robot **401** may further include three motors **406**, which may rotate a solid shaft **408** that is connected with bars **410** to the parallel plate **404**. The "delta" or "spider" cutting robot **401** may then move freely in the x-, y-, and z-direction within a moving envelope. In certain examples, the moving envelope may be about 200 mm in the z-direction, and about 600-800 mm in the x- and y-direction.

[0049] As illustrated in FIG. 4b, the cutting robot **400** may be a four degrees of freedom cutting robot **412**, where the additional degree of freedom allows the four degrees of freedom cutting robot **412** to cut a fish fillet **101** at a certain angle. In such an embodiment, the four degrees of freedom cutting robot **412** may include a motor **414** at the top of the base plate **402** that can rotate the shaft **416**. The shaft **416** may be connected to a perpendicular gear **418** that is connected to a parallel plate **404**. A cutting head **420** may be connected to the perpendicular gear **418**, such that a rotation of the cutting head **420** can be performed. In some examples, the cutting head **420** can rotate around any axis in its moving envelope that is parallel to the x-axis.

[0050] In some embodiments, the cutting robot **400** may be a six degree of freedom cutting robot (not shown). A six degree of freedom cutting robot may be able to move freely in the x-,

y-, and z-direction, and also be able to rotate around the x-, y-, and z-axis to perform arbitrary cuts.

[0051] In some embodiments, during cutting procedures, an alignment and orientation of each fish fillet **101** with respect to the cutting conveyor **214** may be at least substantially preserved. In some embodiments, the alignment and/or orientation of the fish fillet **101** may be disturbed. In particular embodiments, the cutting machine **216** may include a scraper located proximate a top surface of the cutting conveyor **214**. The scraper may be so located as to contact the now cut portions **117** of the fish fillet **101** and to generally realign portions **117** that have moved out of the original alignment and orientation.

[0052] Referring to again to **FIG. 2**, the cutting machine **216** may include an automatic removal section **244**. Alternatively, the automatic removal section **244** may be located outside the cutting machine **216**, but preferably closely proximate the cutting machine **216** with the cutting robot **400**. The automatic removal section **244** may include at least one robotic arm **500** (as described in more detail below in **FIG. 6**) following the at least one cutting robot **400** of the cutting machine **216**, for removing cut portions **117** of a fish fillet **101** having bones. A robotic arm **500** of a food processing apparatus **200** may also be, for example, a grading robot **224**, as described in further detail below (e.g., needle grading robot **600**, two-degree of freedom grading robot **700**, three degrees of freedom grading robot, four degrees of freedom grading robot (**FIGs. 9(i-k)**), gripper grading robot **601**, or spray-removal robot **651** (**FIG. 7a**).

[0053] In some embodiments, the cutting machine **216** communicates with the robotic arm **500**, for example, via a computer receiving an input signal from the cutting machine **216**, and delivering an output signal to the robotic arm **500**. For example, the cutting machine **216** may communicate to the robotic arm **500** the location, alignment, and/or orientation of portions **117** cut according to the cutting pattern employed by the cutting machine **216**, and may also communicate the identification of portions **117** containing bones or other undesirable attributes, so that such portions can be removed by the robotic arm **500**.

[0054] The removal process may be performed while the cut fish fillets **101** are still on the cutting conveyor **214**, as the most accurate information about the precise location of the portions **117** and bones is available. The computer may control the at least one robotic arm **500** and direct the at least one robotic arm **500** to grip portions **117** of a fish fillet **101** having bones, and to remove the portions **117** from the cutting conveyor **214**. For example, portions **117** of the fish fillets **101** known to have bones (e.g., a pin bone section) may be automatically removed by the at least one robotic arm **500**. Furthermore, portions **117** of the fish fillets **101** that are indicated as having bones in the first x-ray image or 3D image may be removed.

[0055] **FIG. 5** is a perspective view of a robotic arm **500** of the food processing apparatus **200** of **FIG. 2**. In some embodiments, at least one robotic arm **500** may grip a portion **117** of a cut fish fillet **101**, and slide the portion **117** off of a side of the cutting conveyor **214** into a first conveyor or tray **252**.

[0056] As shown in FIG. 5, a robotic arm 500, located in the automatic removal section 244 and proximate the exit of the cutting machine 216, may include a gripper 502, a first motor 504, a second motor 506, a first control arm 508, and a second control arm 510. The first control arm 508 may be coupled to the first motor 504 at a first end of the first control arm 508, and may be coupled to the gripper 502 at a second end of the first control arm 508. The second control arm 510 may be coupled to the second motor 506 at a first end of the second control arm 510, and may be coupled to the gripper 502 at a second end of the second control arm 510. The first motor 504 and second motor 506 may be controlled by a computer. The first motor 504 may rotate the first control arm 508 about the first end of the first control arm 508. The second motor 506 may rotate the second control arm 510 about the first end of the second control arm 510. When the first ends of the first and second control arms 508, 510 are rotated, the second ends of the first and second control arms 508, 510 may manipulate the gripper 502. For example, the computer may control the first and second motors 504, 506 to move the first and second control arms 508, 510, respectively, and, in turn, manipulate the gripper 502 to grip portions 117 of a cut fish fillet 101 containing bones. The computer may further manipulate the gripper 502 to dispose the portions 117 of the fish fillet 101 containing bones in a first conveyor or tray 252. In some embodiments, the gripper 502 is rotated with an actuator; for example and without limitation, an air cylinder, motor, linear motor, traditional motor, or solenoid (not shown in images).

[0057] In particular embodiments, the gripper 502 may include a hook that can be slipped under a portion 117 to be removed, or stuck into the portion 117 to be removed. In particular embodiments, the gripper 502 may include at least two members that can clamp or press the portion 117 between the two members. In particular embodiments, the gripper 502 may include a suction member that uses a vacuum to suck the portion 117 against the gripper 502. In particular embodiments, the at least one robotic arm 500 may include the robotic gripper unit described in U.S. Patent Application Publication No. 2012/0307013 A1, and/or may include the associated gripper described in U.S. Patent Application Publication No. 2012/0307013 A1. In particular embodiments, the at least one robotic arm 500 may be replaced with at least one grading robot 224, which is described above and in further detail below in relation to FIG. 6 and FIG. 9.

[0058] In some embodiments, the first conveyor or tray 252 may comprise a box, bin, tub, and/or basket. In some embodiments, the at least one robotic arm 246 may grip a portion 117 and lift the portion 117 off of the cutting conveyor 214 and subsequently place the portion 117 in the first conveyor or tray 252. In some examples, the alignment and orientation of the portions 117 of the fish fillet 101 not containing bones are not substantially disturbed during the removal process. In other words, an alignment and orientation of the portions 117 not containing bones may be preserved, while portions 117 containing bones are removed. The removal process may be fully automatic, and may be controlled by the computer, for example, based on at least one of the first x-ray image, 3D image, and cutting pattern of each fish fillet 101. In some embodiments, the cutting machine 216 may include a robotic arm 500 similar to the any of the robotic arms described in U.S. Patent Application Publication No. 2012/0307013 A1.

[0059] The food processing apparatus 200 may optionally include a check section 254 following the cutting machine 216 and automatic or manual removal section 244. In some embodiments, the cutting machine 216 may not include the at least one robotic arm 246, and the check section 254 may serve to remove portions 117 of a fish fillet 101 containing an undesirable component; for example, bones. In some embodiments including the at least one robotic arm 246, the check section 254 may be utilized to ensure that after the fish fillet 101 has been cut, and portions 117 removed by the at least one robotic arm 246, that all portions 117 containing bones have been removed. Portions 117 containing bones that are removed in the check section 254 and placed in a second conveyor or tray 253. In some examples, the check section 254 is a manual check section 254. In some embodiments, the food processing apparatus 200 may not include a check section 254, and may include just the at least one robotic arm 246 for removing portions 117 of fish fillets 101 having bones. All portions 117 of a fish fillet 101 placed in the first and second conveyors or trays 252, 253 may then be taken to be used in other products and applications. The alignment and orientation of the remaining portions 117 may be preserved.

[0060] As shown in FIG. 2, a fish fillet 101 may be moved into a second x-ray machine 217. The second x-ray machine 217 may function the same as the first x-ray machine 212, with similar components, and may take a second x-ray image of the fish fillet 101. The second x-ray machine 217 may x-ray and capture second x-ray images of the remaining portions 117, which may be oriented parallel to each other, in series with each other, or both. The second x-ray machine 217 may transfer the second x-ray images to the computer. The computer may be programmed to determine, based on the second x-ray images from the second x-ray machine 217, whether any bones remain in any of the remaining portions 117 of the fish fillet 101. Furthermore, the computer may be programmed to determine from the second x-ray images whether the fish fillet 101 has been advanced cut by the cutting machine 216.

[0061] In some embodiments, the second x-ray images may be utilized by the computer, for example and without limitation, to control a pull-back conveyor (not pictured) that directs portions 117 that still contain bones onto another conveyor (not pictured) while the remaining portions 117 that are bone-free may move onto the grading conveyor 218. In some examples, the bones from the portions 117 that still contain bones may be manually removed, and the manually-processed portions 117 may be moved again through the second x-ray machine 217. By way of further example, the second images may be utilized to provide feedback to the computer controlling the cutting robot 400 about the performance of the cutting. In certain examples wherein the cutting machine 216 has a tendency to leave bones in portions that are supposed to be bone-free, this feedback is important for correcting this tendency, but the feedback may also assist in optimizing yield.

[0062] Optimization of the yield following the cutting process occurs when there is some error rate in which operation of the cutting robot 400 fails to completely cut away all of a bone or bone fragment into a portion for removal. For example, when a computer is controlling the cutting robot 400 to make the closest cut possible to the bone or bone fragment, the rate of

errors is likely to increase. Conversely, when a computer is controlling the cutting robot **400** to minimize the occurrence of such errors, the amount of flesh left in portions **117** containing bones is likely to increase. Therefore, in some embodiments, the second x-ray images may be utilized to provide feedback to the computer controlling the cutting robot **400** about the error rate, and the computer controlling the cutting robot **400** may adjust the operation of the cutting robot **400** to approach an optimal error rate (e.g., a non-zero rate of bones and bone fragments remaining in cut portions **117**).

[0063] Further optimization of the yield can be obtained by inspecting the portions **117** containing bones that are identified by the second x-ray machine **217**, as the characteristics of the extra tissue on those portions can then be evaluated.

[0064] In some embodiments, the remaining portions **117** of the fish fillet **101** may move from the cutting conveyor **214** to the grading conveyor **218**, while at least substantially maintaining the alignment and orientation of the remaining portions **117**. The grading conveyor **218** may be larger in width than the cutting conveyor **214**, to allow for more portion positions **256** during the grading process, as described in further detail below. Furthermore, the grading conveyor **218** may include one or more sub-conveyors in series. In some embodiments, one or more sub-conveyors forming the grading conveyor **218** may vary in size and rate of movement. The grading conveyor **218** may feed the remaining portions **117** of the fish fillet **101** through a rejection section **220**. The rejection section **220** may remove an entire fish fillet **101** from the grading conveyor **218** that, for some reason, may not have been cut into portions **117** in the cutting machine **216**. For example, the rejection section **220** may include a scraper to slide an uncut fish fillet **101** off of the grading conveyor **218** and into a tray or onto a separate conveyor for further processing. The rejection section **220** may send data to a computer about an uncut fish fillet **101**, and the computer may be programmed to adjust or improve cutting procedures based on the data.

[0065] As shown in FIG. 2, a fish fillet **101** may be moved into to a second imaging system **235**, which may function the same as the first imaging system **234**, with similar components. For example, a laser **304** may illuminate the portions **117**, and a 3D camera **302** may transfer a 3D image to a computer programmed to determine features comprising, for example and without limitation, the location of fat, color, gaping, and other visual defects. In some examples, the second imaging system **235** captures a 3D image of a portions **117** as the portion **117** is disposed on a receiving conveyor, before the fish fillet **101** is subject to any further manipulations that may alter its alignment and/or orientation (e.g., a grading conveyor **218**). Using certain wavelengths, the laser **304** may provide a 3D image utilized by the computer to detect parasites. From any and all of the foregoing information, the computer may adjust grading procedures (described in further detail below), for example, to grade the portions **117** according to these features.

[0066] In some embodiments, the remaining portions **117** of the fish fillet **101** may move from the second imaging system **235** into one or more further cutting machines **216**, either directly, or after or betwixt grading procedures. In particular embodiments, the computer uses the

information gathered from processing the 3D image to adjust or control cutting procedures in a further cutting machine **216**.

[0067] In embodiments, the grading conveyor **218** may feed the portions **117** of a cut fish fillet **101** through a grading section **222** of the food processing apparatus **200**. The grading section **222** may include at least one grading robot **224**, at least one tub **258** beneath the grading conveyor **218**, and a plurality of processing conveyors **226**. As the remaining portions **117** pass under the grading robot(s) **224**, the computer may direct the grading robot(s) **224** to move portions **117** of a fish fillet **101**. The grading robot **224** may be selected from the group consisting of a needle grading robot **600**, as described further below with respect to FIG. 6; a two-degree of freedom grading robot **700**, as described further below with respect to FIG. 9; a three degrees of freedom grading robot; a four degrees of freedom grading robot; a gripper grading robot **601**; and a spray-removal robot **651** (FIG. 7a) as described further below.

[0068] Referring to FIG. 7a, a spray-removal robot **651** may include at least one valve **661** that ejects a fluid (e.g., water) from a nozzle **663** towards a first conveyor **665** (which may be the grading conveyor **118**), and at least one actuator (e.g., air cylinder, motor, linear motor **655** with at least one guide member **657**, traditional motor, and solenoid).

[0069] The mounting member **653** may extend up from a base member of the conveyor **665** and/or **667**, and may extend above the conveyor **665** and/or **667**. The support member **659**, to which the spray-removal robot **651** is attached, may be horizontally mounted to the mounting member **653**, with the nozzle **663** directed towards the first conveyor **665**. The support member **659** may be sufficiently spaced from the top surface of the conveyor **665** and/or **667**, such that a portion **117** may pass under the support member **659** and attached valve(s) **661**. The linear motor **655** may drive the sliding of valve **661** back and forth along the guide member **657** in at least substantially horizontal directions.

[0070] A computer may control the operation of the spray-removal robot **651**. In operation, the computer may determine a location of a portion **117** to be removed from one or more of: information from the second imaging system **235**, the second x-ray image, 3D image, first x-ray image, a signal from the cutting robot **400**, movement of the cutting conveyor **214**, and movement of the grading conveyor **218**. Based on the estimated location of the portion **117** to be removed, the computer may cause the linear motor **655** may drive the sliding of a valve **661** horizontally along the guide member **657** until the valve **661** is oriented over a projected path of the section of the portion **117** to be removed.

[0071] Once a valve **661** has been oriented over the projected path of the portion **117** to be removed, the computer may determine, for example, based on the foregoing criteria, exactly when the portion **117** will be in a location and position where the valve **661** can eject fluid through the nozzle **663** to impact the portion **117**. Then, the nozzle **663** is controlled to eject fluid along the desired path, and to shut off the fluid when the desired path is completed. In some examples, there may be multiple spray-removal robots **651** where each spray-removal robot **651** has attached a valve **661** and a nozzle **663**, and, for example, be disposed to eject

fluid at the same time to impact the same section of the portion 117 to be removed, or to impact multiple sections to be removed at the same time.

[0072] According to one mode of operation, the cut portions 117 are brought by the first conveyor 665 towards the spray-removal robot 651, and the receiving conveyor 667. The receiving conveyor 667 may convey portions 117 thereon, for example, to an X-ray machine 217, a further grading section 122, a realigning apparatus 800, or to any other conveyor where is to take place further grading, processing, and/or packaging of a fillet 101.

[0073] When the computer determines from one or more of the second x-ray image, 3D image, first x-ray image, a signal from the cutting robot 400, movement of the cutting conveyor 214, and movement of the grading conveyor 218, that the location of a section of the portion 117 to be removed (containing bones or exhibiting other undesirable attributes) is the location to be impacted by fluid ejected from the nozzle 663, the computer may then cause the valve 661 to eject fluid through the nozzle 663. When the section of the portion 117 to be removed is impacted by the fluid stream, it may be forced into the space between the first conveyor 665 and the receiving conveyor 667, such that the portion 117 to be removed will not be moved to the receiving conveyor 667, and other portions 117 of the fillet 101 are moved by the motion of the first conveyor 665 onto the surface of the receiving conveyor 667. The spray-removal robot 651 may optionally include a laser sensor to detect the location, alignment, and/or orientation of portions 117 on the receiving conveyor 667.

[0074] As shown in FIG. 7b, in particular embodiments, a spray-removal robot 651 may be used to remove portions 117 that have been cut by the cutting machine 216 at an angle 675 with respect to the first conveyor 665. For example, the computer that controls the operation of the spray-removal robot 651 may utilize information from a laser sensor and/or preceding elements of the system 200 (e.g., the cutting robot 400) to identify a portion 117 removed, wherein the position of the portion 117 is described by a plane bisecting the portion 117 at the angle 675. In particular examples, the portion 117 to be removed is the pinbone portion of a fish fillet 101. In such examples, angled cuts were made to track one or more particular feature(s) in the portions 117 for removal; for example, bones, such as the pinbone of a fish fillet 101. Referring to FIG. 7d, in some modes of operation, the ejection of fluid from the nozzle 663 can be controlled, such that a portion 117 defined by a partial cut 673 (i.e., starting and/or ending within the fillet 101) is made, for example, to leave the fillet 101 intact around the volume of the cut.

[0075] The ejected fluid from the spray-removal robot 651 removes the portion 117 to be removed from the remainder of the fillet 101. In particular embodiments, the portion 117 to be removed is removed from the conveyor system by a force acting upon the section, which may be in addition to, or separate from, the force from the ejected fluid. In one embodiment, there may be sufficient space between the distal end of the first conveyor 665 and the proximal end of the receiving conveyor 667, such that a portion 117 to be removed can be forced into the space between the first conveyor 665 and the receiving conveyor 667, where gravity pulls the section down and away from the conveyors through the space between the distal end of the

first conveyor **665** and the proximal end of the receiving conveyor **667**. Referring to **FIG. 8a**, in one embodiment, there is a shaft **671** between the conveyors that aids in pulling down the section to be removed, for example, by increasing the space between the distal end of the first conveyor **669** and the proximal end of the receiving conveyor **667** and **668**.

[0076] In some modes of operation, if the space between the distal end of the first conveyor **669** and the proximal end of the receiving conveyor **667** and **668** is increased sufficiently to aid in the removal of particular portions **117**, the transfer of the remaining portions **117** from the first conveyor **665** to the receiving conveyor **667** may be negatively impacted by the spacing; for example, the transfer may not maintain accurate location and/or alignment of portions **117**. Therefore, in particular embodiments, a plate or conveyor system (**FIG. 8b**) with a slot **670** is positioned between the first conveyor **665** and the receiving conveyor **667**, wherein the slot **670** is sized and positioned for the removal of the portion **117** impacted by the fluid from the spray-removal robot **651**. For example, the slot **670** can be of a size at least as large as the portion **117** to be removed, and it may be moved along with the spray-removal robot **651**, or with an independent actuator or robot. The size of the slot **670** may be fixed, or it may be variable, controlled by an actuator.

[0077] Referring to **FIG. 8(a-b)**, some modes of operation may define the slot **670** between a first receiving conveyor **667** and a second receiving conveyor **668**. The first receiving conveyor **667** and the second receiving conveyor **668** may be moved in the direction perpendicular to the conveyor's movement **119**. The first receiving conveyor **667** and the second receiving conveyor **668** may be moved together in particular embodiments, or independently in other embodiments. When moved together, the slot **670** is always approximately the same width, and the first receiving conveyor **667** and the second receiving conveyor **668** may be moved, such that the slot **670** is beneath the section of the portion **117** to be removed. When the first receiving conveyor **667** and the second receiving conveyor **668** are moved independently, the width of the slot **670** (along with its position beneath the received portions **117**) can be adjusted, for example, according to information from the computer that controls the operation of the spray-removal robot **651**.

[0078] In a grading section **122**, the grading robot(s) **224** may be able to remove portions **117** of a fish fillet **101** still containing bones from the grading conveyor **218** and into the at least one tub **258**. The at least one grading robot **224** may be able to move the portions **117** of a fish fillet **101** directly onto one of the plurality of processing conveyors **226**. The grading robot(s) **224** may be able to move in the direction of movement of the grading conveyor **218**, so that the grading robot(s) **224** remain above the portions **117** while the movement of the portions **117** is carried out.

[0079] In some embodiments, the at least one grading robot **224** may be capable of moving to a side of the grading conveyor **218**, such that the grading robot **224** is not directly above the grading conveyor **218** but rather, may be directly above one of the plurality of processing conveyors **226** or the at least one tub **258**. In some embodiments, a top surface **262** of at least one of the plurality of processing conveyors **226** may be at least substantially coplanar with a

top surface **264** of the grading conveyor **218**. In particular embodiments, the alignment and orientation of the portions **117** of a fish fillet **101** may be substantially preserved when a grading robot **224** moves the portions **117** from the grading conveyor **218** to a processing conveyor **226** having a top surface **262** substantially coplanar with the top surface **264** of the grading conveyor **218**. In particular embodiments, a top surface **262** of the processing conveyor **226** may be lower than the top surface **264** of the grading conveyor **218**, such that, when moved, the portions **117** are slid off the grading conveyor **218** by a grading robot **224** and dropped onto the processing conveyor **226**.

[0080] In some embodiments, a fish fillet **101** may be cut and portions **117** of the cut fish fillet **101** graded at the same time. In particular embodiments, the grading is performed simultaneously as part of the cutting process. For example, the cutting robot **400** may be the same robot as the grading robot **600**.

[0081] In some embodiments, a grading robot **224** may organize the portions **117** of a fish fillet **101** to different areas (portion positions **256**) of the grading conveyor **218** according to different characteristics of the portions **117**. For example, in some embodiments, a grading robot **224** may be controlled to move the tail portion of a fish fillet **101** to a certain portion position **256** of the grading conveyor **218**, and to move all of the loin portions of the fish fillets **101** to another portion position **256** of the grading conveyor **218**. In some embodiments, a grading robot **224** may organize the portions **117** of a fish fillet **101** according to a weight of the portions **117**. For example, the grading robot **224** may be controlled to move all portions **117** having a weight within a first range of weight to a certain portion position **256** of the grading conveyor **218**, and optionally to move all portions **117** having a weight within a second range of weight to another portion position **256** of the grading conveyor **218**. In some embodiments, the at least one grading robot **224** may organize the portions **117** of a fish fillet **101** according to one or more metric and/or criterion of size, type, or quality. The different portion positions **256** of the grading conveyor **218** may be designated as leading to different processes. For example, the different portion positions **256** of the grading conveyor **218** may lead to different processing conveyors **226** or trays, which in turn, may lead to any of multiple different processes. Such processes may include one or more of packaging, breading, freezing, further cutting, and any other known process for food processing.

[0082] In some embodiments, a grading robot **224** may be able to move one or more portion(s) **117** from a group of portions **117** that are oriented parallel to each other without disturbing the alignment and orientation of the other portions **117** in the group. For example, with reference to **FIG. 1**, the grading robot **224** may be able to move portion **117** two from portions **117** four and five, without disturbing the alignment and orientation of portions **117** four and five. In particular embodiments, the alignment and orientation of the cut portions **117** may be substantially preserved when the grading robot **224** moves the portions **117** from the grading conveyor **218**. The substantial preservation of orientation and/or alignment of portions during grading may provide an advantage over previously known grading robots that are limited to grading portions **117** that are in series. For example, previously known grading robots, such as scrapers, move across a conveyor and remove any portions **117** along a path

of the scraper. Thus, previously known grading robots are unable to grade a single portion 117 of a group of portions 117 that are oriented parallel to each other.

[0083] At least one of the grading robot(s) 224 may be able to move a portion 117 of a fish fillet 101 without damaging the delicate flesh of the portions 117. For example, at least one grading robot 224 may be a needle grading robot 600 as described in FIG. 6, which includes at least one needle 602 that can be inserted into the flesh of each portion 117 without damaging the flesh. A computer, based on one or more of the second x-ray image, 3D image, first x-ray image, and estimated location of the portion 117 following the activity of the cutting robot 400, may control the needle grading robot 600 to a location in line with a center area of a portion 117 to be moved. The computer may then control the needle grading robot 600 to lower the needle(s) 602 into the center area of the portion 117 to be moved. The needle grading robot 600 may then be directed to move the portion 117 to a portion position 256, by moving the needle(s) 602 to the portion position 256 without retracting the needle(s) 602 from the portion 117, according to the selected function of the needle grading robot 600.

[0084] Having at least one needle 602 to puncture the portions 117 may provide an advantage over previously known grading robots. For example, previously known robots used to grade delicate food products often damage the flesh by breaking, crushing, or tearing the flesh of the portion 117 while moving the portion 117, for example, by pressing the flesh between two members. On the other hand, by puncturing the portions 117 with at least one needle 602, the flesh may not be broken, crushed, torn, or otherwise damaged. Furthermore, using at least one needle 602 to puncture the portions 117 may allow the alignment and orientation of the portions 117 to be maintained during grading. Contrariwise, pressing the portions 117 between two members can cause folds in the flesh that can disrupt the alignment or orientation of the portions 117.

[0085] In some embodiments, the alignment and orientation of the portions 117 may have to be maintained during the grading process for subsequent processes such as, for example, packaging and freezing processes. Accordingly, moving the portions 117 with at least one needle 602 may also provide an advantage over moving the portions 117 with scrapers, which are often used to move portions 117 of food articles 101 on a conveyor by placing a scraper to one side of the portion 117, and pushing the portion 256 to a desired location. Using a scraper to move the portions 117 can also cause folds in the flesh, which can disrupt the alignment and orientation of the portions 117. On the other hand, using at least one needle 602 to move the portions 117 may help to maintain the alignment and orientation of the portions 117 for further processes. For example, multiple needles 602 may be used to puncture a portion 117 and the multiple needles 602 may be spaced throughout the portion 117. Having multiple needles 602 contacting multiple locations throughout the portion 117 while the portion 117 is moved may assist in maintaining the alignment and orientation of the portion 117 for further processes.

[0086] Referring again to FIG. 6, a needle grading robot 600 may include a first mounting member 603, a second mounting member 604, a first actuator (e.g., air cylinder 606, motor, linear motor, traditional motor, and solenoid), a second actuator 608, a first guide member 610,

a second guide member **612**, a horizontally movable support member **614**, a vertically movable support member **616**, a laser sensor **618**, at least one needle **602**, and a release mechanism **620**.

[0087] The first mounting member **603** and second mounting member **604** may extend up from a base member **622** of the grading conveyor **218**, and may extend above the grading conveyor **218**. The first guide member **610** may be horizontally mounted to the first mounting member **603** and the second mounting member **604**. The first guide member **610** may be sufficiently spaced from the top surface of the grading conveyor **218**, such that a portion **117** may pass thereunder. A length of the first guide member **610** may be longer than a width of the grading conveyor **218**, such that the first guide member **610** extends out past the first and second mounting members **603**, **604**, and extends out past side surfaces of the grading conveyor **218** to allow for a grading robot **224** to place a portions **117** directly onto processing conveyors **226** next to the grading conveyor **218**, as discussed above.

[0088] The horizontally movable support member **614** may be slidable back and forth along the first guide member **610** in at least substantially horizontal directions. The second guide member **612** may be mounted to the horizontally movable support member **614**. The vertically movable support member **616** may be slidable up and down along the second guide member **612** in at least substantially vertical directions.

[0089] The first air cylinder **606** may be attached at one end to the horizontally movable support member **614**, and may be attached at another end to the second mounting member **604**. The second air cylinder **608** may be attached at one end to the second guide member **612**, and attached at another end to the vertically movable support member **616**. At least one needle **602** may be attached to a lowermost portion **624** of the vertically movable support member **616**, and a length of the needle(s) **602** may be oriented in a direction at least substantially normal to the top surface of the grading conveyor **218**. In some examples, the needle(s) **602** may have an outer diameter, for example and without limitation, within a range of 0.5 mm to 2 mm; or within a range of 0.1 mm to 0.4 mm; within a range of 2 mm to 5 mm. The release mechanism **620** may be attached to the lowermost portion **624** of the vertically movable support member **616** proximate at least one needle **602**. The laser sensor **618** may be disposed proximate the second mounting member **604**, and may track the position of the second guide member **612** and vertically movable support member **616**.

[0090] A computer may control the operation of the at least one grading robot **224**. In operation, the computer may determine an estimated location of a portion **117** to be moved based on one or more of the second x-ray image, 3D image, first x-ray image, movement of the cutting conveyor **214**, and movement of the grading conveyor **218**. Based on the estimated location of the portion **117** to be moved, the computer may cause the horizontally movable support member **614** to move horizontally until at least one needle **602** attached to the lowermost portion of the vertically movable support member **624** is oriented over a center of a projected path of the portion **117** to be moved. The laser sensor **618** may be used to determine when the vertically movable support member **616** is correctly oriented over the

center of the projected path of the portion **117**. The horizontally movable support member **614** is moved, for example, by pumping air into or sucking air out of a first air cylinder **606**. By pumping air into or sucking air out of the first air cylinder **606**, the first air cylinder **606** may be caused to extend or retract. By extending or retracting the first air cylinder **606**, the first air cylinder **606** may push or pull the horizontally movable support member **614** along the first guide member **610**. By pushing or pulling the horizontally movable support member **614**, the at least one needle **602** may be moved along the first guide member **610** and across the width of the grading conveyor **218**.

[0091] Once at least one needle **602** has been oriented over the center of the projected path of the portion **117** to be moved, the computer may determine, for example, based on the estimated location of the portion **117** and based on the movement of the grading conveyor **218**, exactly when the portion **117** will be directly underneath the needle(s) **602**. The computer may then cause the vertically movable support member **624** to move downwards towards the portion **117** such that the needle(s) **602** penetrates at least partially the flesh of the portion **117** to be moved. The vertically movable support member **624** is moved downwards by the action of a second actuator, for example, by pumping air into a second air cylinder **608** and extending the second air cylinder **608**. Once the at least one needle **602** has penetrated the flesh of the portion **117** to be moved, that portion **117** can be moved by moving the horizontally movable support member **614** according to the above described procedure.

[0092] After the portion **117** has been moved by a needle grading robot **600**, at least one needle **602** may be retracted from the flesh of the portion **117**. In some embodiments, the procedure may happen naturally, for example, when the portions **117** are dropped into a tub **258**. In such examples, the portions **117** may naturally fall off the needle(s) **602**. In some embodiments, a release mechanism **620** may be used to press against the portion **117** as the at least one needle **602** is lifted. At least one needle **602** may be lifted, for example, by sucking air out of a second air cylinder **608** and retracting the second air cylinder **608**. By retracting the second air cylinder **608**, the vertically movable support member **624**, to which the needle(s) **602** is attached, may be pulled up along the second guide member **612** by the second air cylinder **608**. Once the vertically movable support member **624** has been moved up and the at least one needle **602** retracted from the portion **117**, the grading process may begin again and may repeat the above described process in relation to another portion **117** to be moved.

[0093] In some embodiments, a needle grading robot **600** may include a plurality of needles **602** oriented linearly in a direction parallel to the direction the grading conveyor **218** is moving. In some embodiments, a needle grading robot **600** may include a plurality of needles **602** oriented linearly in a direction perpendicular to the direction the grading conveyor **218** is moving. In some embodiments, a needle grading robot **600** may include a plurality of needles **602** oriented in a shape of one or more of, for example and without limitation, a square, circle, triangle, or cross. For example, the orientation of the plurality of needles **602** may be chosen based on a projected function of a specific needle grading robot **600**. For example, based on the shape of a portion **117** to be moved, certain orientations of the plurality of needles **602** may be better suited to maintain the alignment and orientation of the portion **117**.

[0094] In some embodiments, where the needle grading robot 600 includes a plurality of needles 602, the plurality of needles 602 may all be pointed in a direction substantially normal to the top surface of the grading conveyor 218. In some embodiments, the plurality of needles 602 may be pointed in directions not substantially normal to the top surface of the grading conveyor 218. For example, the plurality of needles 602 may be pointed in directions, such that if the plurality of needles 602 touched the top surface of the grading conveyor 218, an angled formed between each needle 602 of the plurality of needles 602 and the top surface of the grading conveyor 218 would be an acute angle. In some embodiments, the plurality of needles 602 may include crossing needles 602.

[0095] In some embodiments, a grading robot 224 may lift a portion 117 from the top surface of the grading conveyor 218 in order to place the portion 117 in a portion position 256 on the grading conveyor 218, or to lift the portion 117 from the top surface of the grading conveyor 218 to remove the portion 117 from the grading conveyor 218, for example and without limitation, into a tray or bin or onto another conveyor entirely. In particular embodiments, a grading robot 224 that lifts a portion 117 from the top surface of the grading conveyor 218 may comprise a gripper (a "gripper grading robot" 601). As described above with regard to a robotic arm 500, a gripper may include, for example and without limitation, a hook that can be slipped under a portion 117 to be removed, or stuck into the portion 117 to be removed, at least two members that can clamp or press the portion 117 between the two members, a suction member that uses a vacuum to suck the portion 117 against the gripper, and/or any gripper described in U.S. Patent Application Publication No. 2012/0307013 A1.

[0096] As shown in FIG. 6(b), a needle grading robot 600 may be adapted to lift a portion 117 from the top surface of the grading conveyor 218 in order to place the portion 117 in a portion position 256 on the grading conveyor 218, or to lift the portion 117 from the top surface of the grading conveyor 218 to remove the portion 117 from the grading conveyor 218. FIG. 6(c)-(d) show at least one needle 602 attached to a lowermost portion 624 of the vertically movable support member 616 according to particular embodiments. In the needle grading robot 600 of FIG. 6(c), the at least one needle 602 is disposed in eight sets of three needles 602, wherein two sets of three needles 602 are disposed in an area of the distal surface of the lowermost portion 624 of the vertically movable support member 616, and the needles 602 are positioned proximate the vertically movable support member 616. In the needle grading robot 600 of FIG. 6(c), the distal surface of the lowermost portion 624 of the vertically movable support member 616 is separated into four areas.

[0097] To grip a portion 117 to slide or lift the portion 117, the needles 602 are moved to a position distal the vertically movable support member 616, piercing the flesh of the portion 117, as shown in FIG. 6(d). Any method may be used to extend the needles to a position distal the vertically movable support member 616, for example, air compression. The sets of needles 602 shown in FIGs. 6(c)-(d) may be moved separately in some examples, according to the grading application. For example, to move small portions 117 only needle 602 set "one" may be extended; to move a bigger, longer portion 117, both needle 602 sets "one" and "two" may

be extended; and to move a shorter, wider portion 117, both needle 602 sets "one" and "three" may be extended; and to move a longer, bigger portion 117, all of needle 602 sets "one," "two," "three," and "four" may be extended.

[0098] In some embodiments, a needle grading robot 600 or gripper grading robot 601 may be capable of rotation in a plane parallel to the surface of the grading conveyor 218, for example, to orient or reorient a portion 117 on the surface of the grading conveyor 218. For example, as shown in FIG. 4 with regard to a cutting robot 400, the needle grading robot 600 or gripper grading robot 601 may include a motor 414 that can rotate, directly or indirectly, the vertically movable support member 616. Thus, in some examples, the vertically movable support member 616 can rotate around any axis in its moving envelope that is parallel to the x-axis (e.g., the surface of the grading conveyor 218).

[0099] In particular embodiments, a needle grading robot 600 (e.g., as shown in FIGs. 6(c)-(d)) may be utilized to lift a plurality of portions 117, for example, before they are moved to a different position on the top surface of the grading conveyor 218, or removed from the top surface of the grading conveyor 218. Such embodiments may in some examples provide the particular advantage of advantage to increasing capacity, for example, when the plurality of portions 117 are removed from the top surface of the grading conveyor 218. In some examples, a single needle grading robot 600 may be utilized to lift a plurality of portions 117 of a fish fillet 101 that each contain, for example, a bone or bone fragment. For example and without limitation, and with reference to FIG. 1, a single needle grading robot 600 may be utilized to lift portions 117 "ten" and "twelve." In this example, both needle 602 sets "one" and "two" may be utilized to grip portion 117 "ten," and needle 602 set "four" may be utilized to grip portion 117 "twelve." For example and without limitation, the needle grading robot 600 may be moved to the desired position (e.g., a different position on the top surface of the grading conveyor 218, or a position that is removed from the top surface of the grading conveyor 218), and both pieces may be released from the gripper, either individually, or at the same time. By way of further example, the needle grading robot 600 may be moved to a first desired position of a first portion 117 (e.g., a different position on the top surface of the grading conveyor 218), the first portion 117 may be released from the gripper at the first position, the needle grading robot 600 may then be moved to a second desired position of a second portion 117, and the second portion 117 may be released from the gripper at the second position (e.g., a position that is removed from the top surface of the grading conveyor 218).

[0100] By lifting the portion 117 from the top surface of the grading conveyor 218, the grading robot(s) 224 may maintain an orientation of the portion 117 while moving the portion 117 to another conveyor. For example, moving a portion 117 from the grading conveyor 218 to a processing conveyor 126, wherein the top surface 164 of the grading conveyor 118 is substantially coplanar with the top surface 162 of the processing conveyor 126, sliding the portion 117 along the top surfaces of the grading conveyor 218 and another conveyor, may subject the portion 117 to conveyors traveling in different directions when the portion 117 is moved from the grading conveyor 218 to the other conveyor. Accordingly, the portion 117 is likely to at least partially rotate such that the orientation of the portion 117 is disturbed. Thus,

by lifting the portion 117, a change in orientation may be avoided.

[0101] In some embodiments, at least one grading robot 224 may slide the portion 117 along the top surface of the grading conveyor 218 to a portion position 256 on the grading conveyor 218, as described above. In some embodiments, the grading robot(s) 224 may slide the portion 117 completely off of the top surface of the grading conveyor 218 and into a tray or tub 258 or onto another conveyor, as described above. In particular embodiments, a grading robot 224 that slides a portion 117 along the top surface of the grading conveyor 218 to a portion position 256 on the grading conveyor 218 may be a two degrees of freedom grading robot 700.

[0102] As shown in FIG. 9a, an illustrative two degrees of freedom grading robot 700 according to some embodiments may include a horizontal actuator, for example and without limitation, an air cylinder 702, a plate 704, and a sensor 706. The horizontal air cylinder 702 may be capable of movement in arbitrary positions in the direction perpendicular to the direction of movement of the grading conveyor 218. The sensor 706 provides feedback on the actual horizontal position of the plate 704 to a computer. Based on the estimated location of the portion 117 to be moved, the computer may cause the horizontal air cylinder 702 to move the plate 704 to push the portion 117 to another portion position 256 on the grading conveyor 218, or off of the grading conveyor 218, for example and without limitation, into a tray or bin or onto another conveyor entirely. The pushing plate 704 may be so thin that it can potentially be used to go between certain portions 117 when there are more than one piece parallel on the belt.

[0103] In some embodiments, the grading section 122 of the food processing apparatus 100 may include a separating block at any location within the grading section 122. In some embodiments, the separating block may have a triangular shape, and may be suspended above the top surface 164 of the grading conveyor 118, but may be suspended close enough to the top surface 164 of the grading conveyor 118 for the portions 117 of a fish fillet 101 to contact the separating block. In embodiments where the separating block has a triangular shape, the separating block may be pointed (a tip of the triangle pointed) in a direction opposite to the direction in which the grading conveyor 118 is moving. Thus, when a portion 117 of a fish fillet 101 contacts the separating block, the portion 117 may slide along a side of the separating block, and may be moved in a direction perpendicular to the direction in which the grading conveyor 118 is moving and toward an outside edge of the grading conveyor 118, until the portion 117 reaches a base of the separating block. Thus, the separating block may serve to separate portions 117 that are oriented parallel to each other.

[0104] In some embodiments, the base of the separating block may have a width less than the width of the grading conveyor 118, such that the separating block may serve to move the portions 117 to different areas of the grading conveyor 118. In some embodiments, the grading section 122 may include secondary conveyors disposed to either side of the grading conveyor 118 in conjunction with a separating block. In such embodiments, the base of the separating block may have a width that is equal to or wider than the width of the conveyor belt, such that

when a portion 117 of a fish fillet 101 contacts the separating block, the portion 117 is moved off of the grading conveyor 118 and onto one of the secondary conveyors. In some embodiments, the secondary conveyors may move at a rate faster than the grading conveyor 118 to further separate the portions 117 from each other in a direction parallel to the direction in which the secondary conveyors are moving.

[0105] In some embodiments, the grading section 222 may include multiple grading robots 224 that perform different grading functions. For example, a first grading robot 224 may remove portions 117 that contain bones into a tub 258, and a second grading robot 224 may, for example, grade the remaining portions 117 according to type, such as tail portions or loin portions. Furthermore, a third grading robot 224 may, for example, grade each type of portion 117 according to weight. Thus, each portion 117 may be graded according to multiple characteristics. In some embodiments, multiple grading robots 224 may be used to perform a single grading function. For example, multiple grading robots 224 may be used to remove portions 117 having bones, while other multiple grading robots 224 are used to organize the portions 117 according to another characteristic of the portions 117.

[0106] In some embodiments, a first group of grading robots 224 may be located on a first sub-conveyor of the grading conveyor 218 and may be controlled by a computer to perform a first function, and a second group of grading robots 224 may be located on a second subsequent sub-conveyor of the grading conveyor 218 and may be controlled by a computer to perform a second function. In particular embodiments, the first sub-conveyor and second sub-conveyor of the grading conveyor 218 may have different widths to accommodate the first and second functions, respectively. In particular embodiments, the grading conveyor 218 may include additional sub-conveyors with respective groups of grading robots 224 that perform yet other functions. In some examples, each sub-conveyor of the grading conveyor 218 may have a plurality of processing conveyors 226 associated with the sub-conveyor.

[0107] In some embodiments, the alignment and/or orientation of a portion 117 may need to be changed or adjusted to allow for further processing. For example, for processes having in-feeds perpendicular to a direction in which the grading conveyor 218 is moving ("perpendicular in-feeds"), the portion 117 may need to be oriented such that a length of the portion 117 is oriented perpendicular to a direction in which the perpendicular in-feeds are moving, as shown in FIG. 2. In particular embodiments, the food processing apparatus 200 may include at least one realigning section 800 for each process that needs realignment for the process. A realigning section 800 may include at least one realigning apparatus 802. A realigning apparatus 802 is described in further detail in relation to FIG. 10.

[0108] FIG. 10a is a top perspective view of a realigning section 800 according to some embodiments. As shown in FIG. 8, the realigning section 800 may include at least one realigning apparatus 802. The realigning apparatus 802 may be disposed at an end of the grading conveyor 218, and above a perpendicular in-feed processing conveyor 804. The realigning apparatus 802 may include a first mini-conveyor 806, a second mini-conveyor 808, and at least one actuator (e.g., air cylinder 810, motor, linear motor, traditional motor, and

solenoid). The first mini-conveyor **806** and second mini-conveyor **808** may be oriented at an acute angle to each other, such that the first mini conveyor **806** and the second mini conveyor **808** form a V-shape. The first mini-conveyor **806** and second mini-conveyor **808** may be mounted above the perpendicular in-feed processing conveyor **804**, such that a length of each of the first mini-conveyor **806** and second mini-conveyor **808** is at least substantially perpendicular to a length of the perpendicular in-feed processing conveyor **804**, and the direction in which the perpendicular in-feed processing conveyor **804** is moving portions **117**.

[0109] When the first mini-conveyor **806** and second mini-conveyor **808** are oriented such that the first and second mini-conveyors **806**, **808** form a V-shape, a point **816** of the V-shape may be lower than the top surface of the grading conveyor **218**, such that portions **117** may come off of the grading conveyor **218** and drop through an open end **812** of the V-shape and into the V-shape formed by first and second mini-conveyors **806**, **808**.

[0110] One or more of the first mini-conveyor **806** and second mini-conveyor **808** may be mounted above the perpendicular in-feed processing conveyor **804** with a hinge member **814**, such that the surface of the first mini-conveyor **806** and the surface of the second mini-conveyor **808** may be separated to provide a gap through which a portion **117** may fall. For example, the first mini-conveyor **806** may be mounted above the perpendicular in-feed processing conveyor **804** with a hinge member **814**, such that the first mini-conveyor **806** may swing away from the second mini-conveyor **808** and provide a gap through which a portion **117** may fall. In some embodiments, the second mini-conveyor **808** may be mounted above the perpendicular in-feed processing conveyor **804** with a hinge member **814**, such that the second mini-conveyor **808** may swing away from the first mini-conveyor **806** and provide a gap through which a portion **117** may fall. In particular embodiments, both the first mini-conveyor **806** and the second mini-conveyor **808** may be mounted above the perpendicular in-feed processing conveyor **804** with a hinge member **814**, such that the first mini-conveyor **806** may swing away from the second mini-conveyor **808**, and the second mini-conveyor **808** may swing away from the first mini-conveyor **806** to provide a gap through which a portion **117** may fall.

[0111] In operation, for example, a portion **117** may have a width and a length, and the length of the portion **117** may be longer than the width. For some processes subsequent to grading, it may be necessary to orient the portion **117**, such that the length of the portion **117** is at least substantially perpendicular to the direction in which the processing conveyor **804** is moving. To ensure that the portion **117** is oriented correctly, the first mini-conveyor **806** and second mini-conveyor **808** may be oriented to form the V-shape, in order to receive a portion **117** from the grading conveyor **218**. A grading robot **224** may organize the portion **117**, such that the portion **117** will be dropped through the open end **812** of the V-shape, and into the V-shape formed by the first mini-conveyor **806** and second mini-conveyor **808**. Belts on the first mini-conveyor **806** and second mini-conveyor **808** may rotate to receive the portion **117**, and to spread the portion **117** along the first mini-conveyor **806** and second mini-conveyor **808**. The V-shape formed by the first mini-conveyor **806** and second mini-conveyor **808** may tend to urge the portion **117** towards the point **816** of the V-shape, and to orient the portion **117** linearly along a length of the first mini-conveyor **806** and second mini-conveyor **808**. Furthermore, the V-shape formed

by the first mini-conveyor **806** and second mini-conveyor **808** may tend to orient the length of the portion **117**, such that the length of the portion **117** is substantially parallel to the lengths of the first mini-conveyor **806** and second mini-conveyor **808**, and at least substantially perpendicular to the length of the perpendicular in-feed processing conveyor **804** and the direction in which the perpendicular in-feed processing conveyor **804** is moving portions **117**. Thus, when a gap is formed between the first mini-conveyor **806** and second mini-conveyor **808**, the portion **117** will drop onto the perpendicular in-feed processing conveyor **804** with the length of the portion **117** oriented substantially perpendicular to the direction in which the perpendicular in-feed processing conveyor **804** is moving portions **117**. As discussed above, orienting the lengths of portions **117** to be perpendicular to the direction in which the perpendicular in-feed processing conveyor **804** is moving portions **117** may be necessary for subsequent processes such as packaging and freezing processes.

[0112] As shown in FIG. 10b, a food processing apparatus **200** according to some embodiments may include at least one additional realigning section **800**. In particular embodiments, the food processing apparatus **200** comprises at least one additional realigning section **800** to realign a portion when the capacity of the first realigning section **800** is exceeded. A food processing apparatus **200** may include one or more transfer conveyor **818** that directs a portion **117** to the next realigning section **800**. A next realigning section may, for example and without limitation, realign a portion **117** onto a next processing conveyor (not shown), or realign a portion **117** into a container **820** that the portion **117** is to be packed in. A food processing apparatus **200** may also include a packing conveyor **822** that can be used to move the container **820** to the correct location to receive the portion **117**. In some examples, the packing conveyor **822** moves such that the portion **117** is placed at a specific x-coordinate in the container **820**. In some examples, the time at which the realigning apparatus **802** is opened is controlled, such that a specific y-position of the portion **117** in the container **820** is selected. The container **820** may either be filled completely, or partially filled. For example, the container **820** may be partially filled, and a grader (not shown) may be used to fill container **820** completely.

[0113] While embodiments (not all of them according to the claimed invention) have been illustrated and described in detail in the drawings and foregoing description, such illustration and description are to be considered illustrative or exemplary and not restrictive; the invention is not limited to the particularly described examples, but to the subject-matter of the appended claims.

REFERENCES CITED IN THE DESCRIPTION

Cited references

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Patent documents cited in the description

- [US7258237B \[0003\]](#)
- [WO2016139611A2 \[0005\]](#)
- [US20120307013A1 \[0041\] \[0045\] \[0045\] \[0045\] \[0046\] \[0047\] \[0057\] \[0057\] \[0058\]](#)

Non-patent literature cited in the description

- Robotic Packaging of Poultry productsK. **KHODABANDEHLOO**Department of Mechanical EngineeringUniversity of Bristol19920000 [\[0004\]](#)
- Benefits of Experts robots intelligence vs. SkillK. **KHODABANDEHLOO**Department of Mechanical EngineeringUniversity of Bristol19920000 [\[0004\]](#)

Patentkrav

1. Fremgangsmåde til sortering af en fødevare (101), hvilken fremgangsmåde omfatter:
 - 5 anvendelse af en sorteringsanordning (224) til at fjerne mindst én af en flerhed af portioner (117) af en fødevare (101) fra overfladen af en sorteringstransportør (118; 218), mens de resterende portioner (117) af fødevareren (101) overføres til en modtagende transportør (667, 668),
 - 10 kendetegnet ved, at sorteringsanordningen (224) omfatter en spraybaseret fjernelsesrobot (651), der omfatter en ventil (661) og en dyse (663), således at ventilen (661) udstøder fluidum gennem dysen (663) for at ramme en position i sorteringstransportørens (118; 15 218) bane, når den portion, der skal fjernes, befinder sig i positionen, hvor den portion, der skal fjernes, drives frem gennem et mellemrum mellem sorteringstransportøren (118; 218) og den modtagende transportør (667, 668), når den portion, der skal 20 fjernes, rammes af fluidum, der udstødes gennem dysen (663).
 2. Fremgangsmåde ifølge krav 1, hvorved den spraybaserede fjernelsesrobot (651) kan flyttes, således at forskellige positioner på sorteringstransportørens (118; 218) bane kan 25 rammes af fluidum, der udstødes gennem dysen (663).
 3. Fremgangsmåde ifølge krav 2, hvorved bevægelsen af den spraybaserede fjernelsesrobot (651) styres af en computer ifølge en bestemmelse af en placering af den portion (117), der skal 30 fjernes, hvor computeren bestemmer placeringen af den portion (117), der skal fjernes, ud fra ét eller flere input, der er valgt fra gruppen bestående af et røntgenbillede, et 3D-billede, et signal fra en skærerobot, bevægelsen af sorteringstransportøren (118; 218) og bevægelsen af en anden 35 transportør eller flere andre transportører, der befinder sig før den spraybaserede fjernelsesrobot (651).
 4. Fremgangsmåde ifølge krav 1, hvorved hver portion i

flerheden af portionerne (117) har en justering og en orientering i forhold til overfladen af sorteringstransportøren (118; 218) og er placeret parallelt med hinanden på overfladen af sorteringstransportøren (118; 218),

- 5 hvor ingen af de resterende portioner i flerheden af portioner (117), som er placeret parallelt med hinanden på overfladen af sorteringstransportøren (118; 218), i det væsentlige flyttes under fjernelsen af portionen (117) fra overfladen af sorteringstransportøren (118; 218), og
- 10 hvor justeringerne og orienteringerne af de resterende portioner i flerheden af portioner (117), som er placeret parallelt med hinanden på overfladen af sorteringstransportøren (118; 218) i det væsentlige opretholdes efter fjernelsen af portionen (117) fra positionen på overfladen af sorteringstransportøren (118;
- 15 218) og overførslen af de resterende portioner i flerheden af portioner (117) til den modtagende transportør (667, 668).

5. Fremgangsmåde ifølge krav 1, hvorved den portion, der skal fjernes, er én af en flerhed af portioner af fødevaren (101),

20 der er placeret parallelt med hinanden og i serie med hinanden på overfladen af sorteringstransportøren (118; 218), hvor portionen på hver side grænser op til en anden portion.

6. Fremgangsmåde ifølge krav 1, hvorved den spraybaserede

25 fjernelsesrobot (651) ydermere omfatter mindst ét monteringselement (653), mindst én aktuator (608; 608; 655), mindst ét styreelement (610, 612; 657) og et vandret bevægeligt bæreelement (614).

30 7. Fremgangsmåde ifølge krav 6, hvorved aktuatoren er en lineær motor (655).

8. Fremgangsmåde ifølge krav 4, hvorved den portion (117), der flyttes, grænser tæt op til andre portioner på modstående sider

35 i en orientering, der i det væsentlige er vinkelret på den parallelle orientering af flerheden af portioner (117).

9. Fremgangsmåde ifølge krav 3, der ydermere omfatter

udvælgelse af den portion (117), som skal fjernes, ud fra mindst ét kriterium, der er valgt fra gruppen bestående af størrelse, vægt, kvalitet og type.

5 10. Fremgangsmåde ifølge krav 9, hvorved kriteriet er typen af et eksisterende ben.

11. Sorteringsanordning (224) til sortering af en fødevare, hvilken anordning omfatter:

10 en sorteringstransportør (118; 218) og
en modtagende transportør (667; 668),
kendetegnet ved, at

sorteringsanordningen (224) ydermere omfatter mindst én
spraybaseret fjernelsesrobot (651),

15 hvor den spraybaserede fjernelsesrobot (651) omfatter mindst én
ventil (661) med en dyse (663), hvor ventilen (661) udstøder
væske gennem dysen (663) for at ramme en position i
sorteringstransportørens (118; 218) bane, mindst ét
monteringselement (653), mindst én aktuator, mindst ét
20 styreelement (610, 612; 657) og mindst ét vandret bevægeligt
bæreelement (614).

12. Sorteringsanordning (224) ifølge krav 11, hvor den
spraybaserede fjernelsesrobots aktuator er valgt fra gruppen
25 bestående af en luftcylinder (606, 608), en motor, en lineær
motor, en traditionel motor og en spole.

13. Sorteringsanordning (224) ifølge krav 11, hvor aktuatoren
er en lineær motor.

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14. Sorteringsanordning (224) ifølge krav 11, hvor den
sprøjtebaserede fjernelsesrobot (651) ydermere omfatter et
bæreelement, som kan flyttes i en retning, der i det væsentlige
er vinkelret på det vandret bevægelige bæreelement.

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15. Sorteringsanordning (224) ifølge krav 11, der ydermere
omfatter en lasersensor (618).

16. Apparat til forarbejdning af fødevarer (200), hvilket apparat omfatter:

mindst én transportør (208, 214)

en skæremaskine (216), og

5 sorteringsanordningen (224) ifølge krav 11.

17. Apparat til forarbejdning af fødevarer (200) ifølge krav 16, der ydermere omfatter:

mindst ét element, der er valgt fra gruppen bestående af

10 mindst ét billeddannelsessystem (234, 235)

mindst ét genomstillingsapparat (802)

mindst én røntgenmaskine (212, 217)

mindst én manuel kvalitetskontrolstation (254)

mindst én automatiseret kvalitetskontrolstation (244), og

15 mindst én yderligere sorteringsanordning (600; 601; 700).

18. Apparat til forarbejdning af fødevarer ifølge krav 17, hvor den yderligere sorteringsanordning er en nålesorteringsanordning (600), en gribersorteringsanordning (601), en sorteringsanordning med to frihedsgrader (700), en sorteringsanordning med tre frihedsgrader eller en sorteringsanordning med fire frihedsgrader.

19. Apparat til forarbejdning af fødevarer ifølge krav 16, der ydermere omfatter mindst én computer, som er programmeret til at betjene den spraybaserede fjernelsesrobot (651) ifølge ét eller flere input, der er valgt fra gruppen bestående af et røntgenbillede, et 3D-billede, et signal fra en skærerobot, bevægelsen af sorteringstransportøren (118; 218) og bevægelsen af en anden transportør eller flere andre transportører, der befinder sig før den spraybaserede fjernelsesrobot (651).

DRAWINGS

Drawing

FIG. 1.

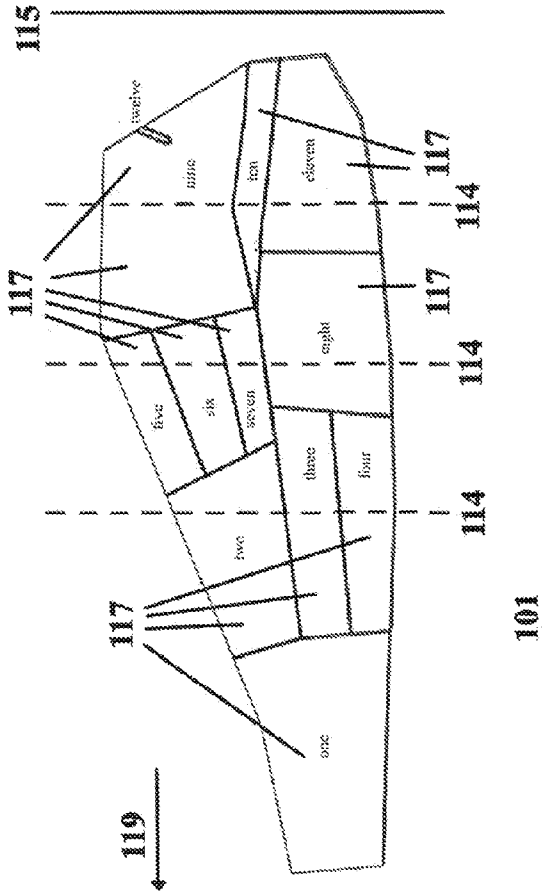


FIG. 2.

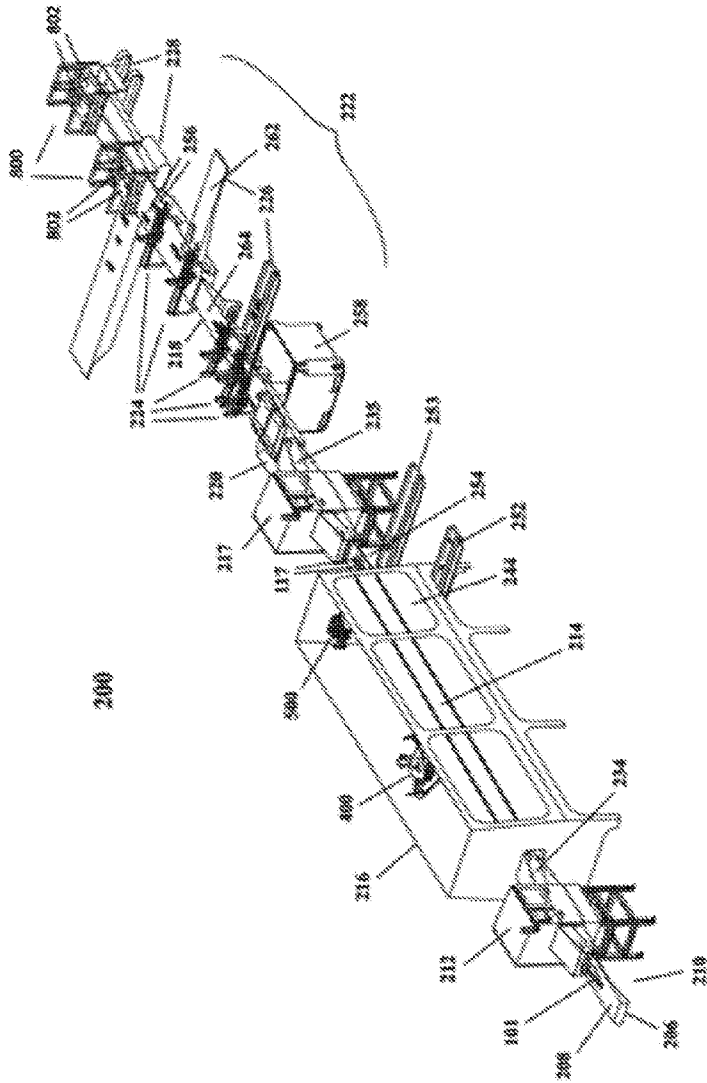


FIG. 3.

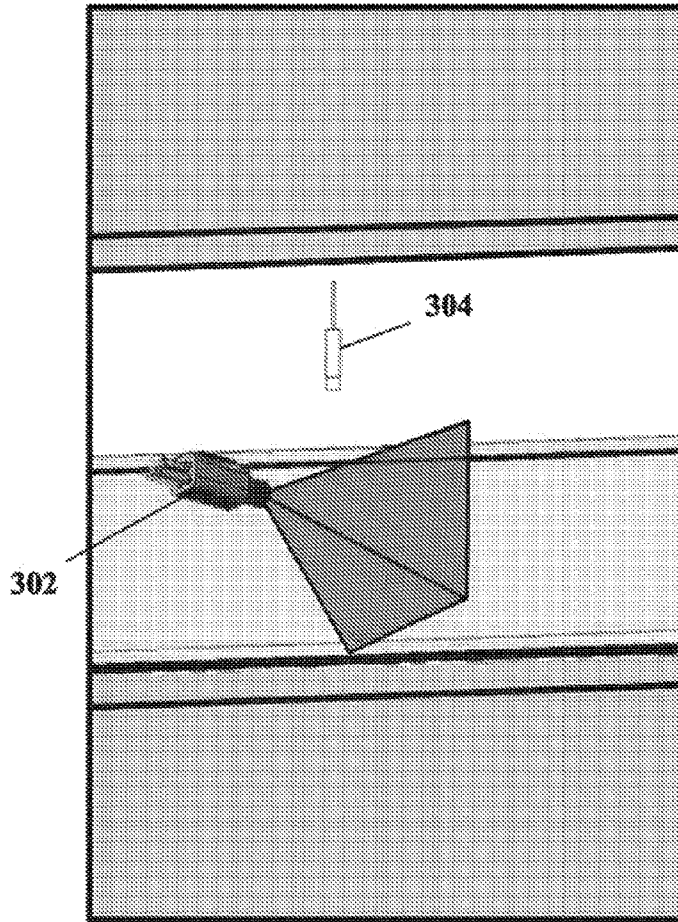


FIG. 4a.

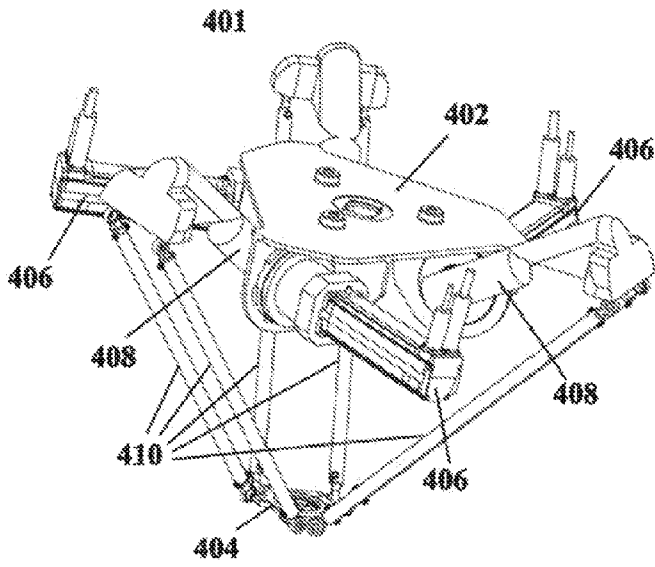


FIG. 4b.

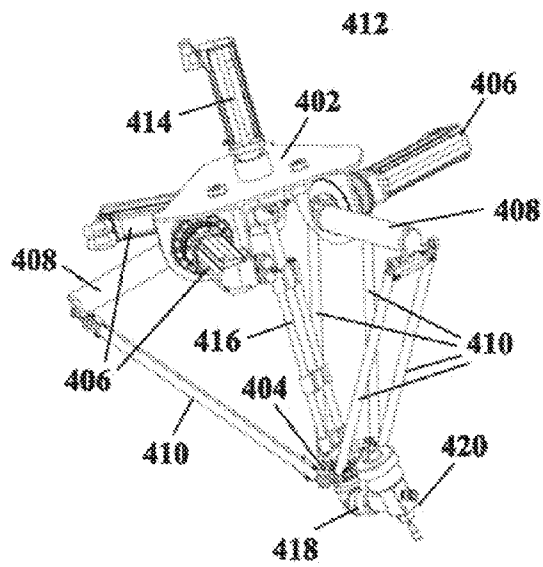


FIG. 5.

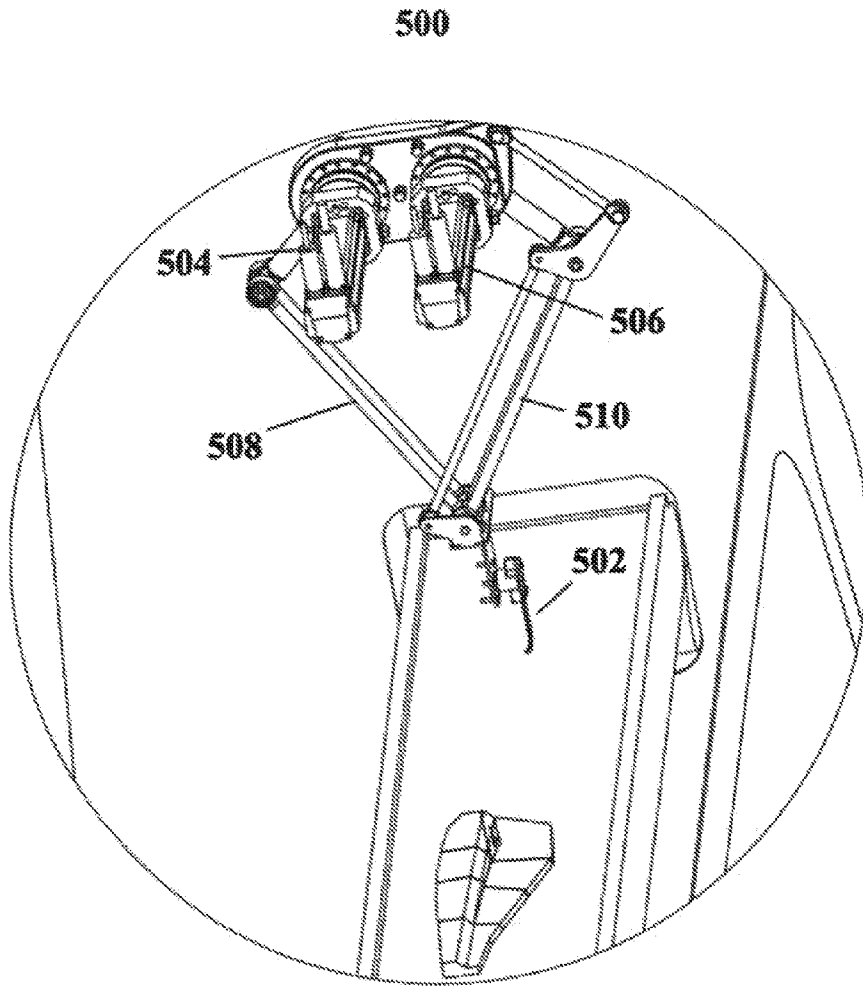


FIG. 6a.

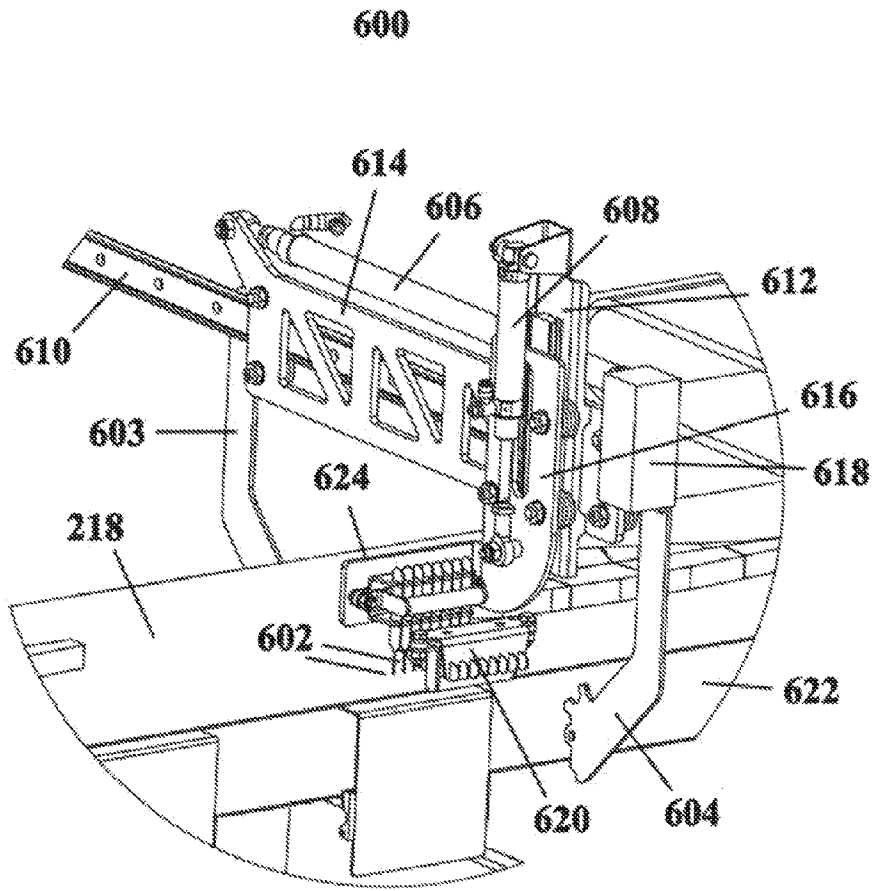


FIG. 6b.

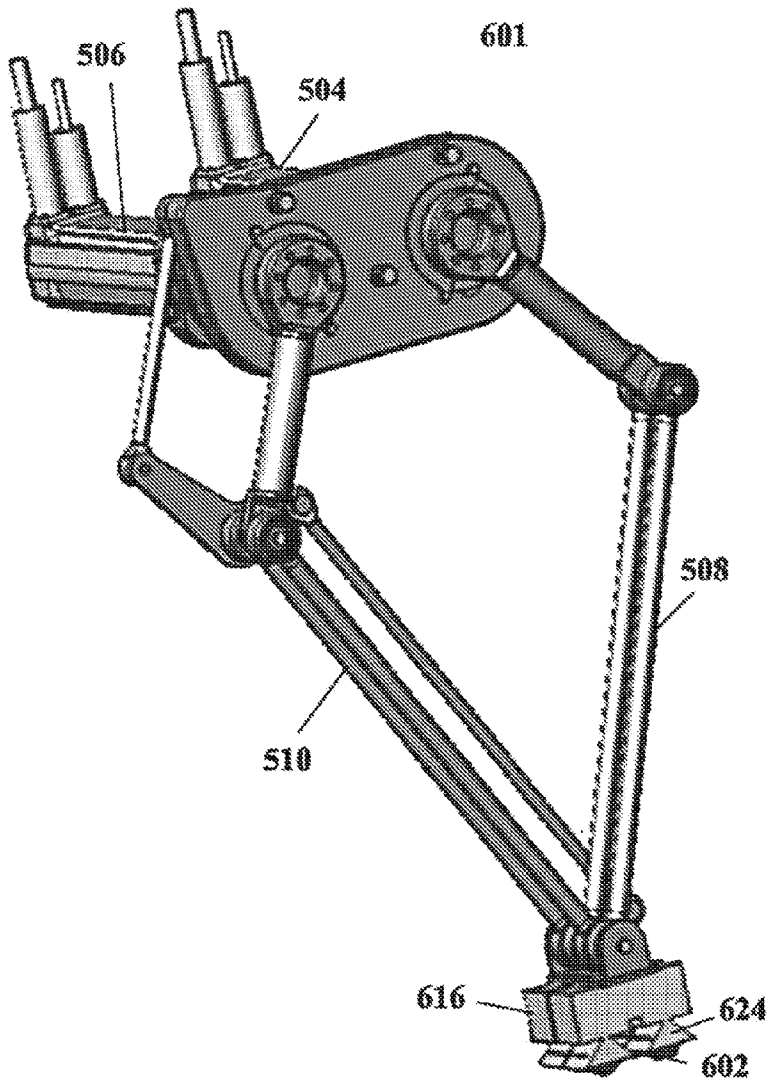


FIG. 6c.

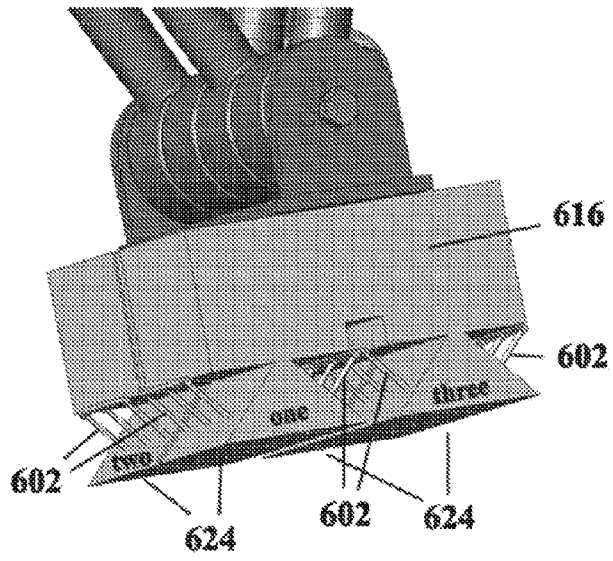


FIG. 6d.

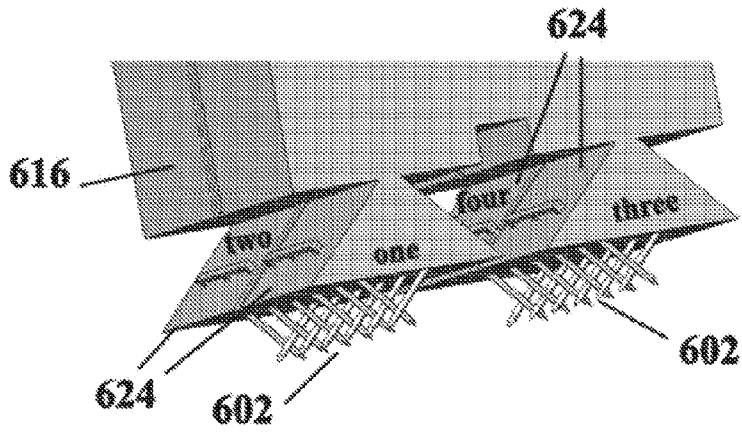


FIG. 6e.

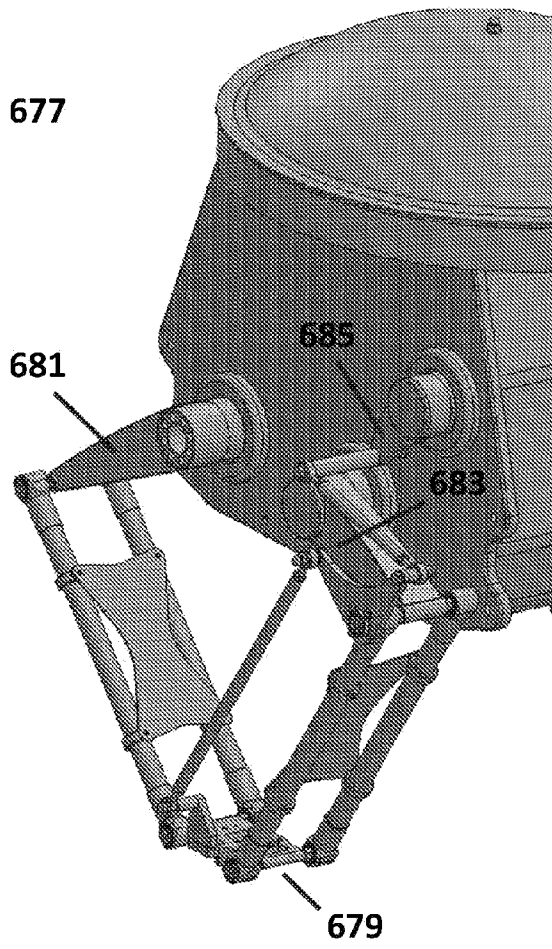


FIG. 7a.

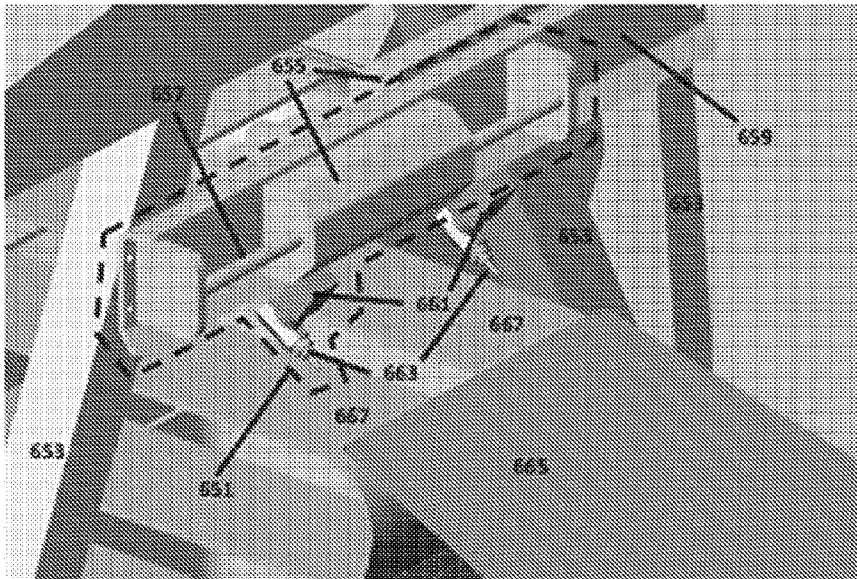


FIG. 7b.

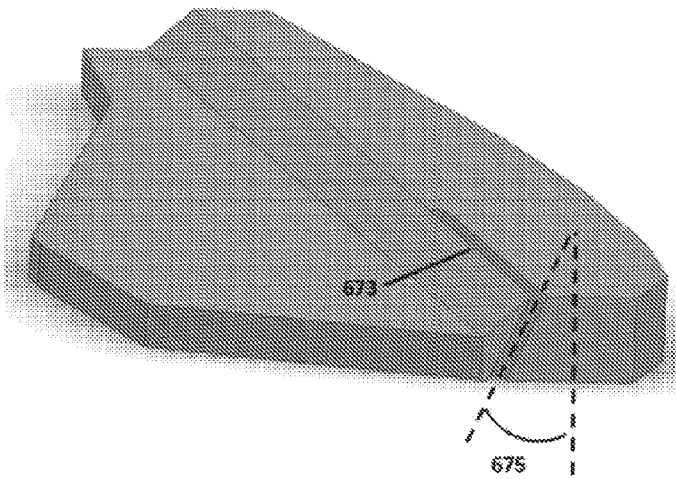


FIG. 7c.

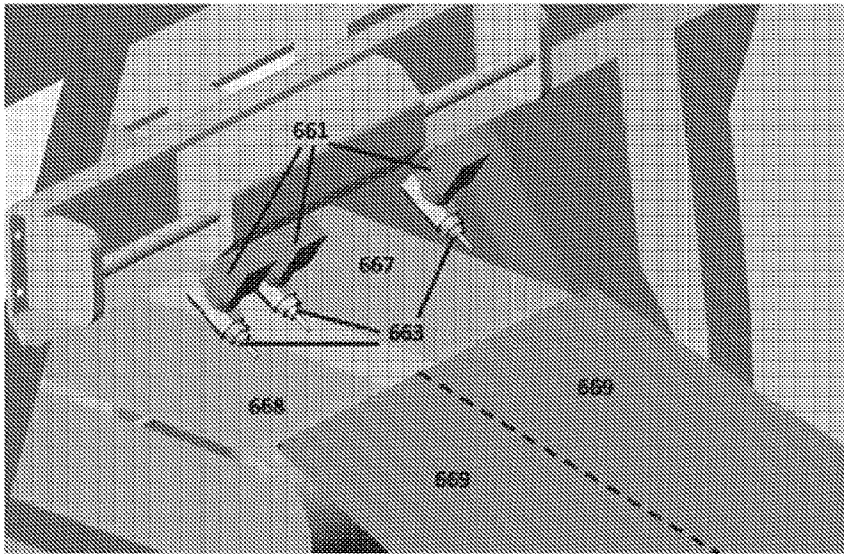


FIG. 7d.

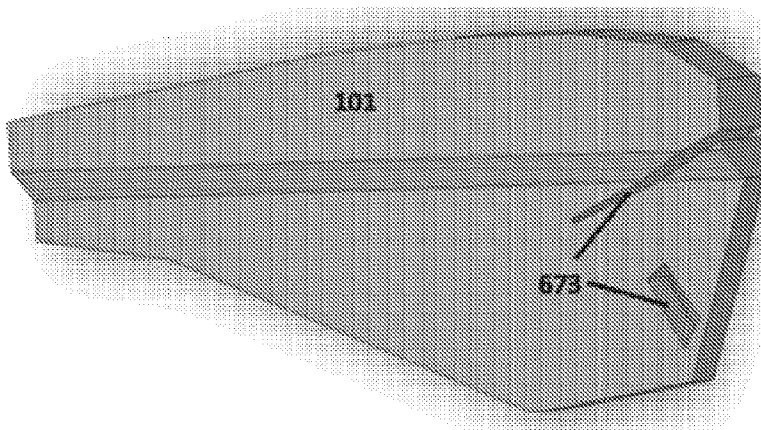


FIG. 8a.

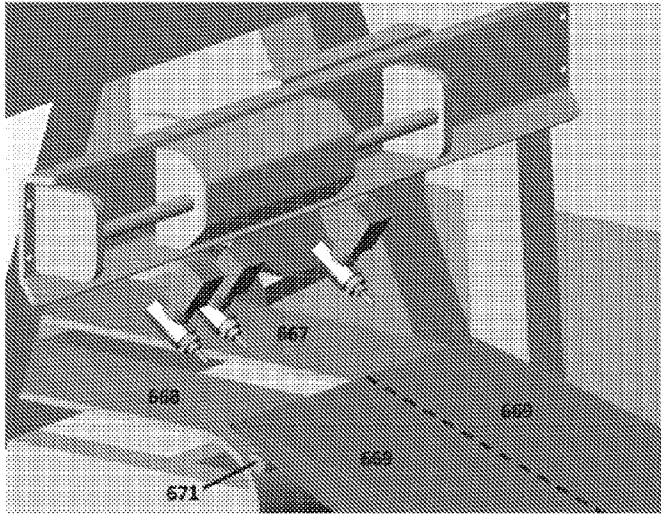


FIG. 8b.

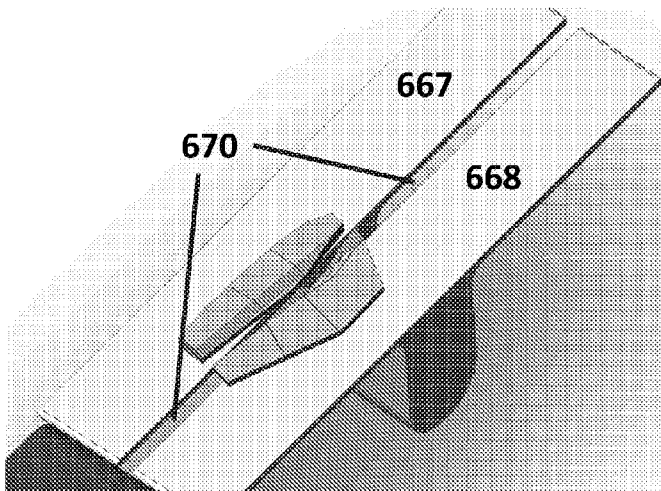


FIG. 9a.

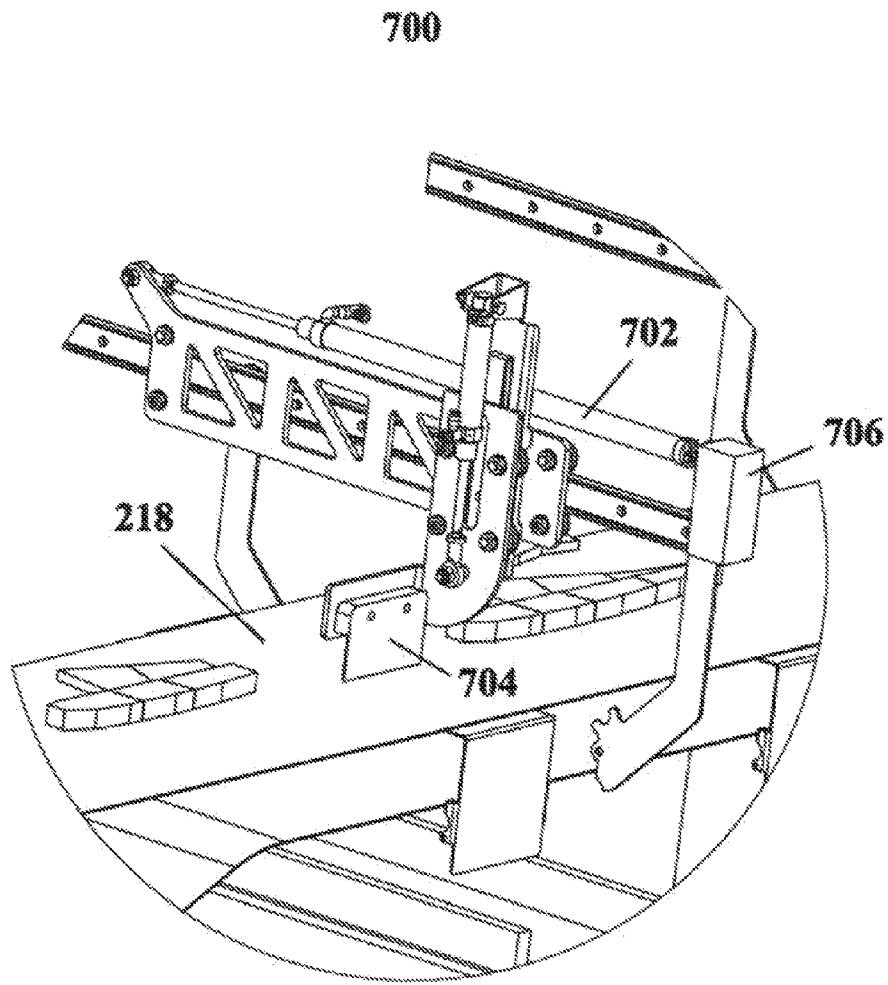


FIG. 9b.

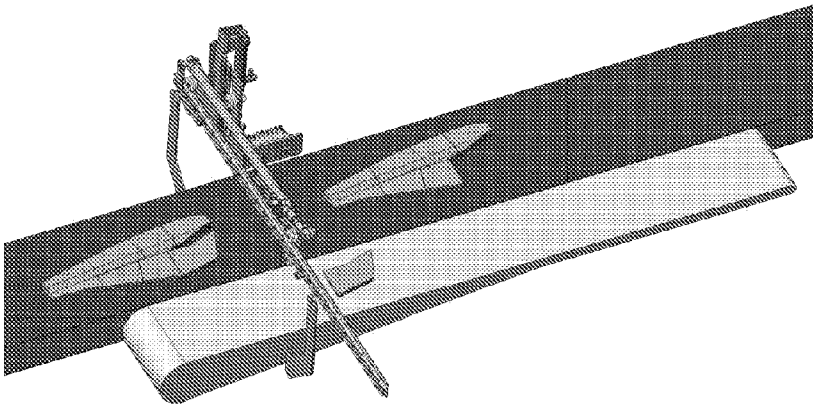


FIG. 9c.

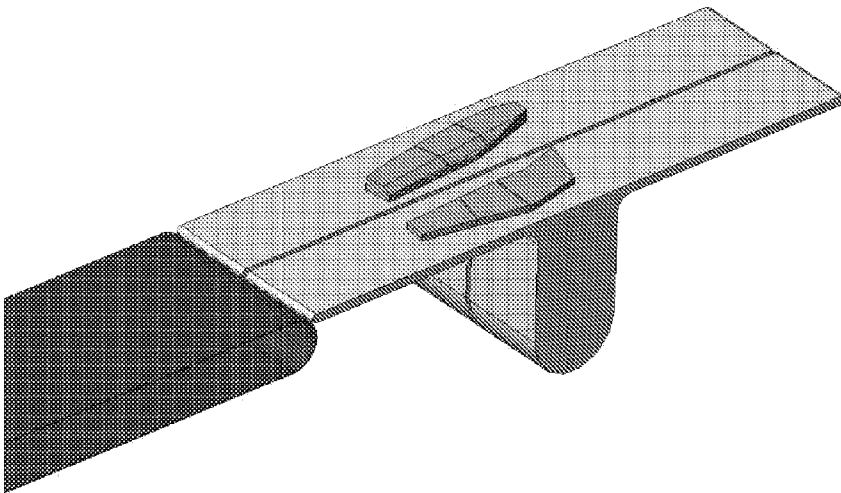


FIG. 9d.

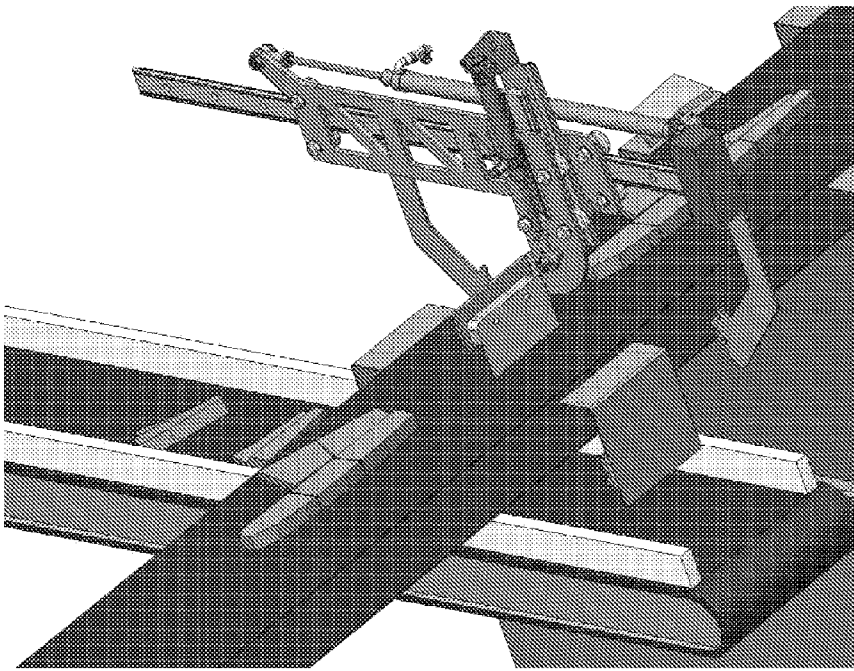


FIG. 9e.

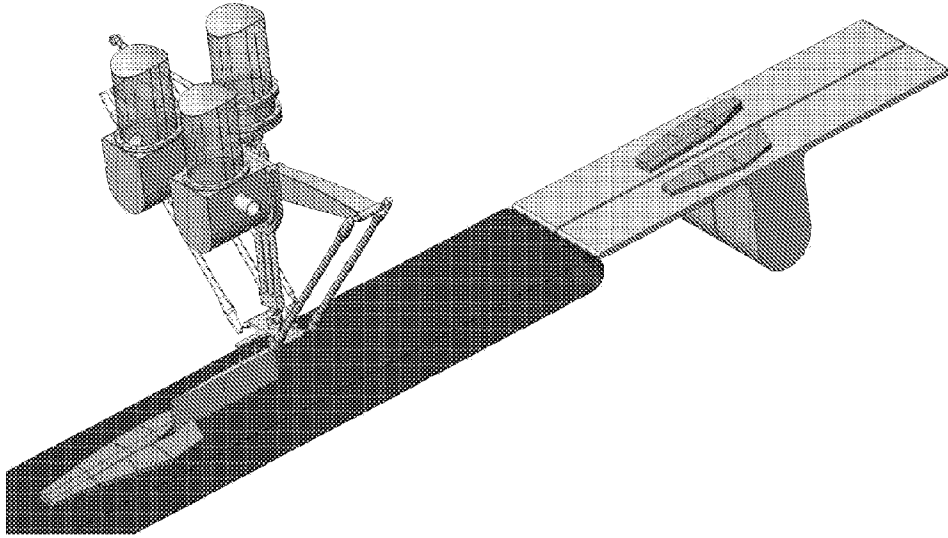


FIG. 9f.

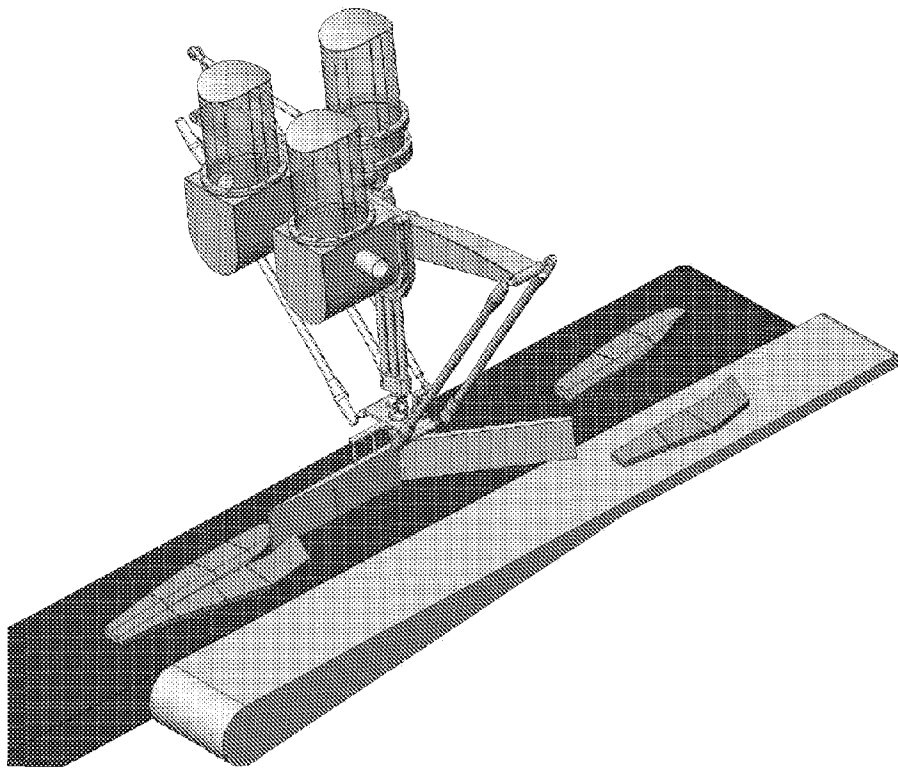


FIG. 9g.

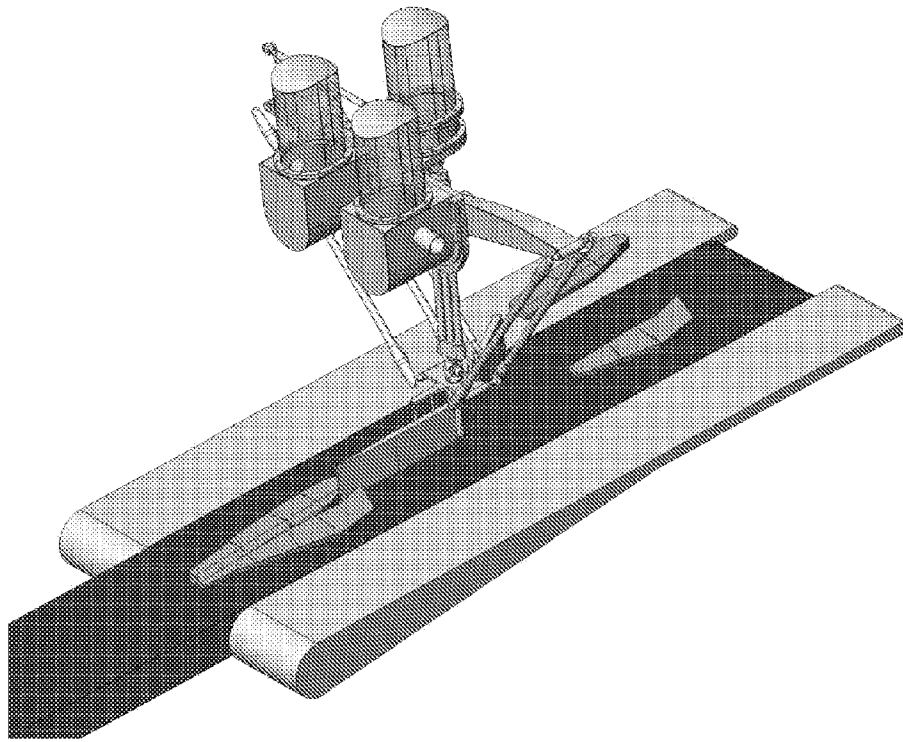


FIG. 9h.

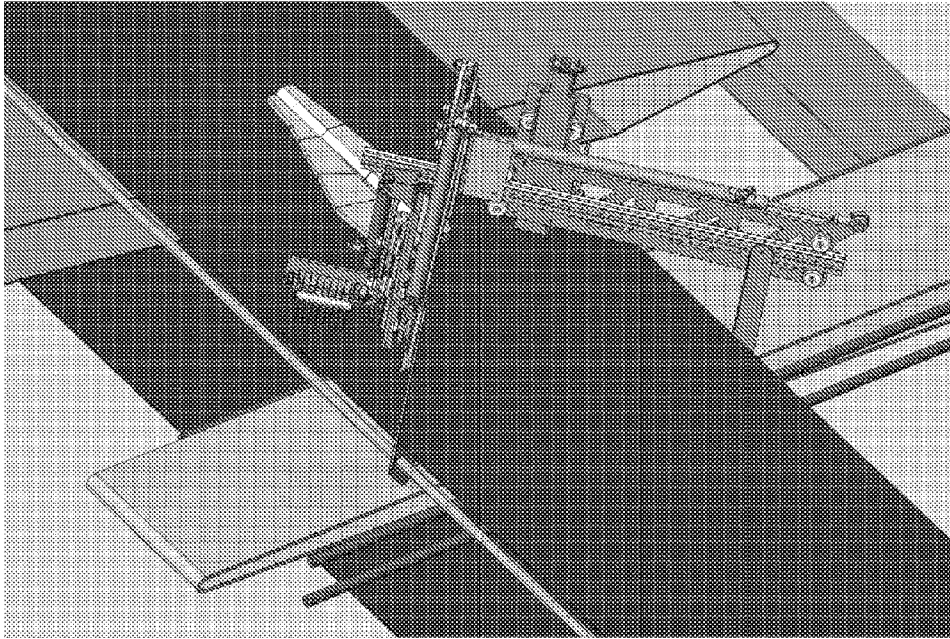


FIG. 9i.

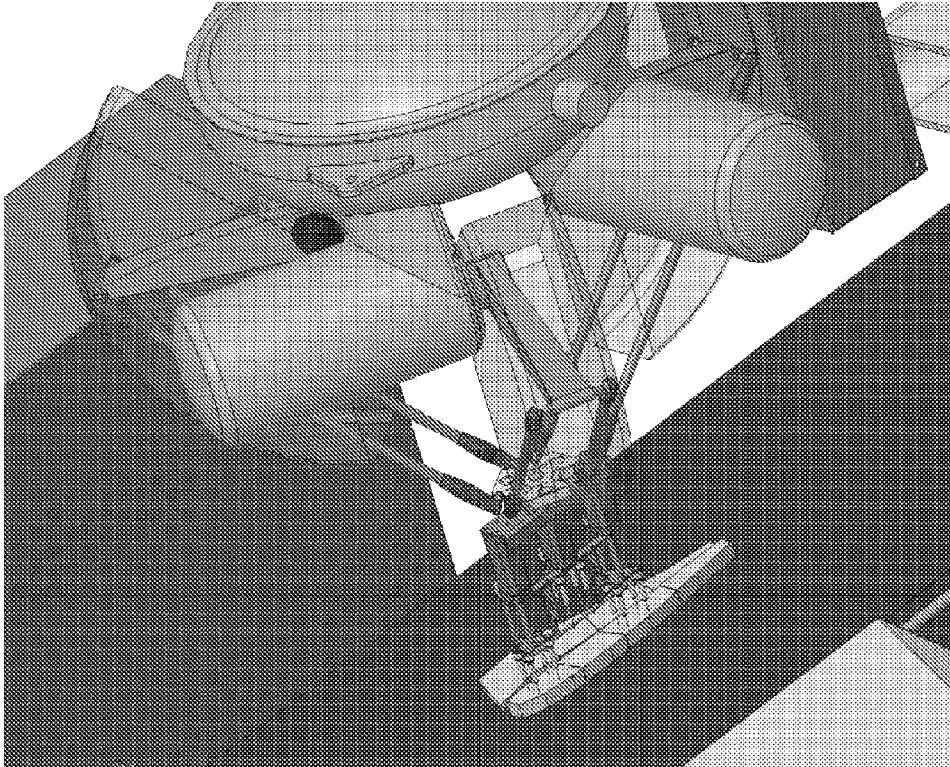


FIG. 9j.

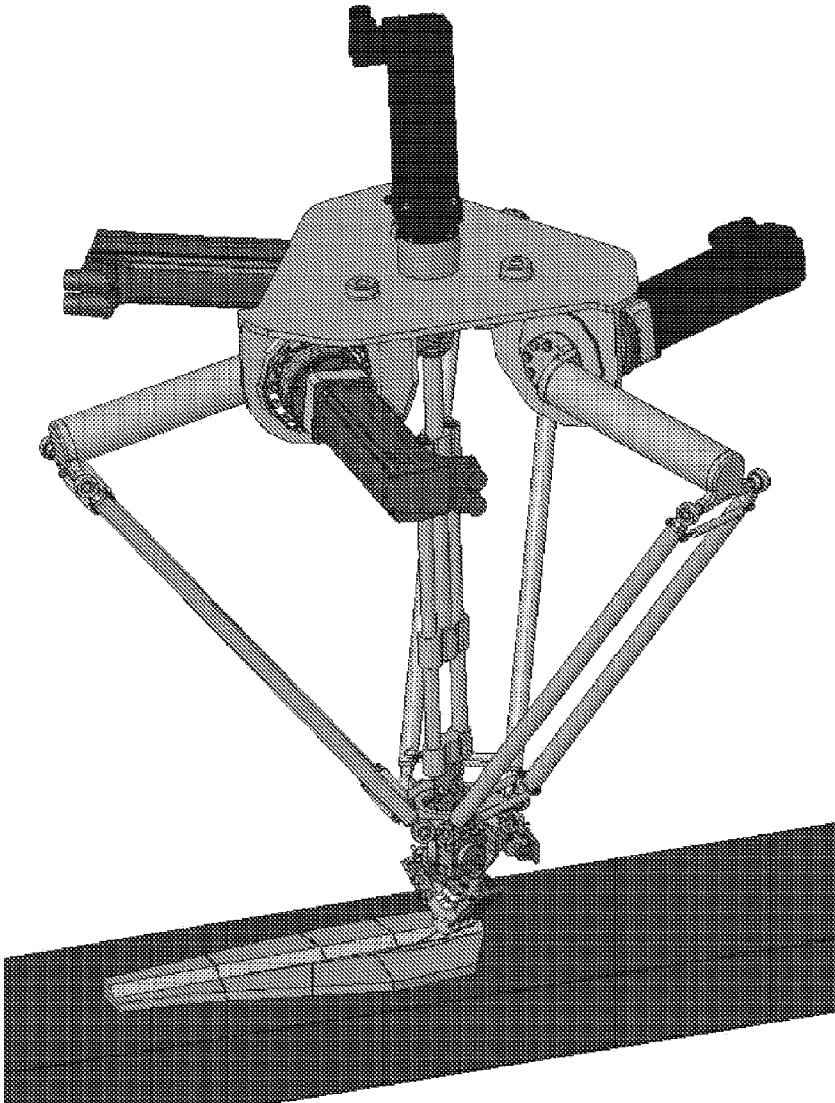


FIG. 9k.

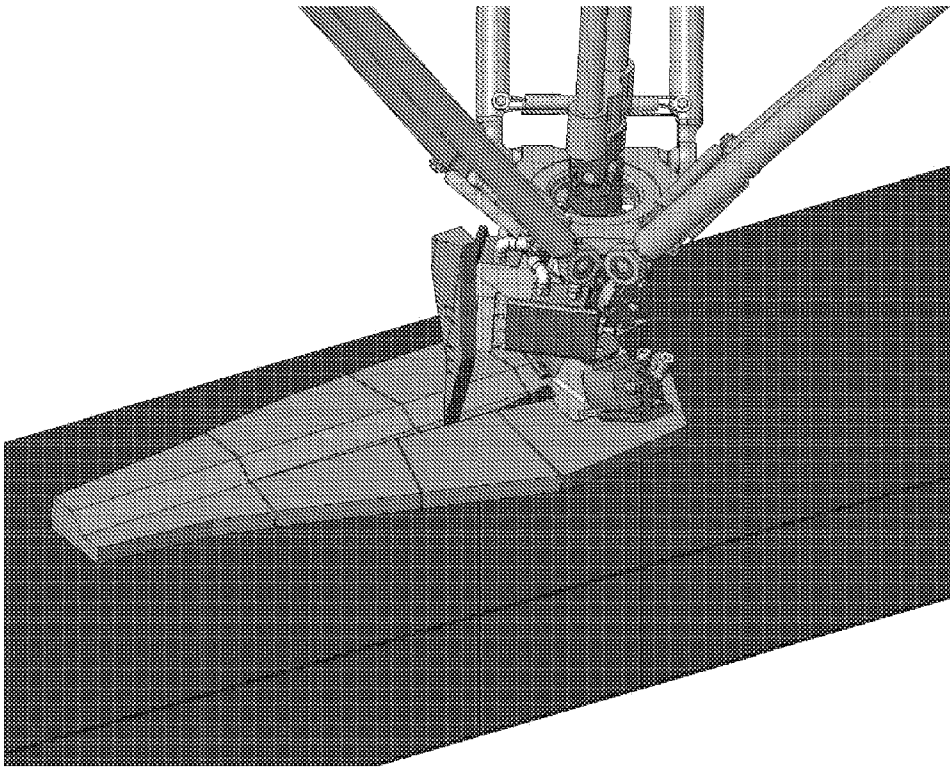


FIG. 10a.

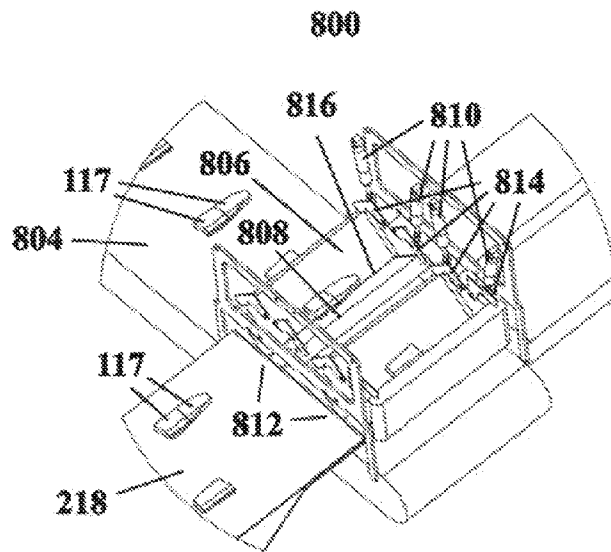


FIG. 10b.

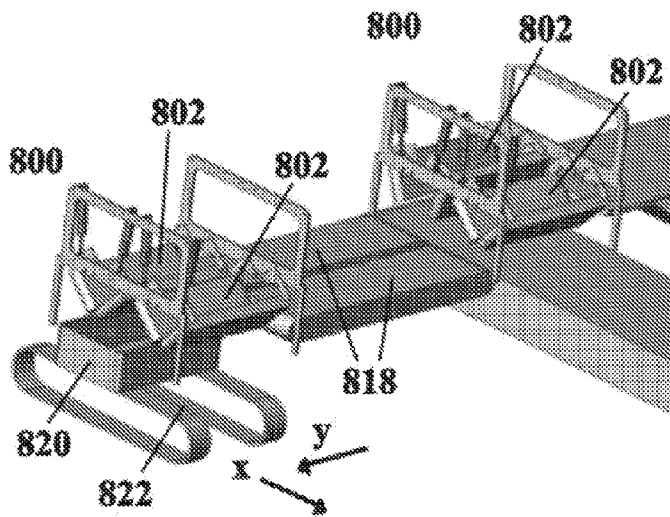


FIG. 11a.

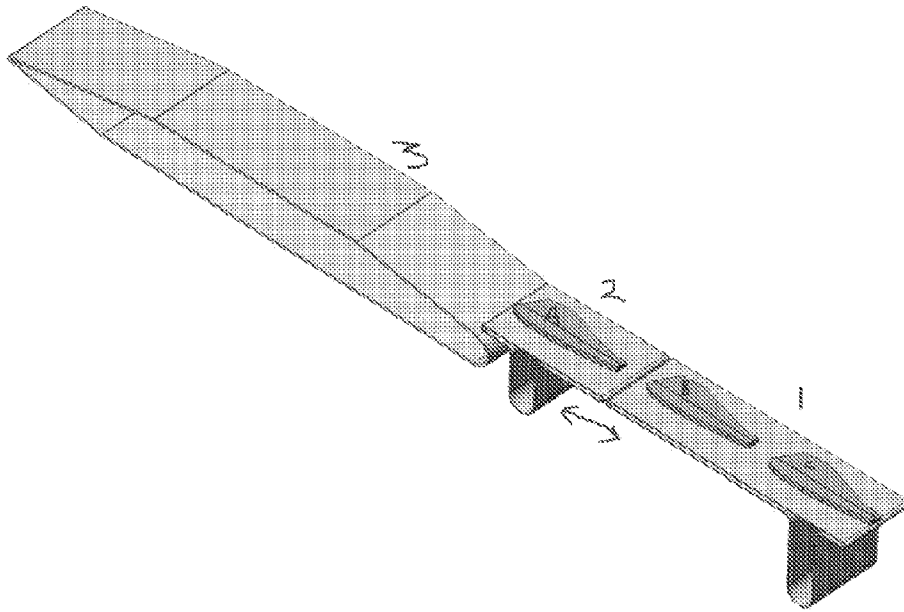


FIG. 11b.

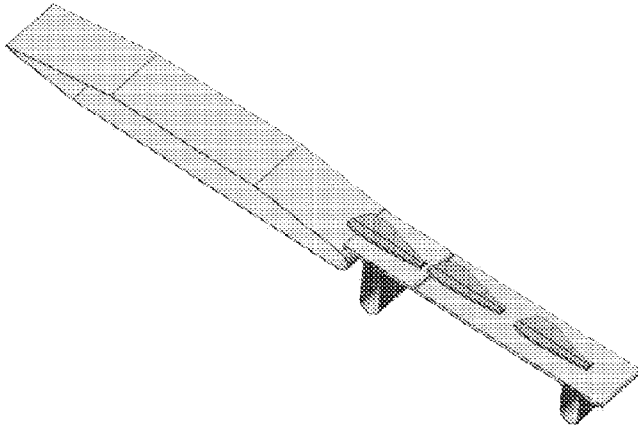


FIG. 11c.

