

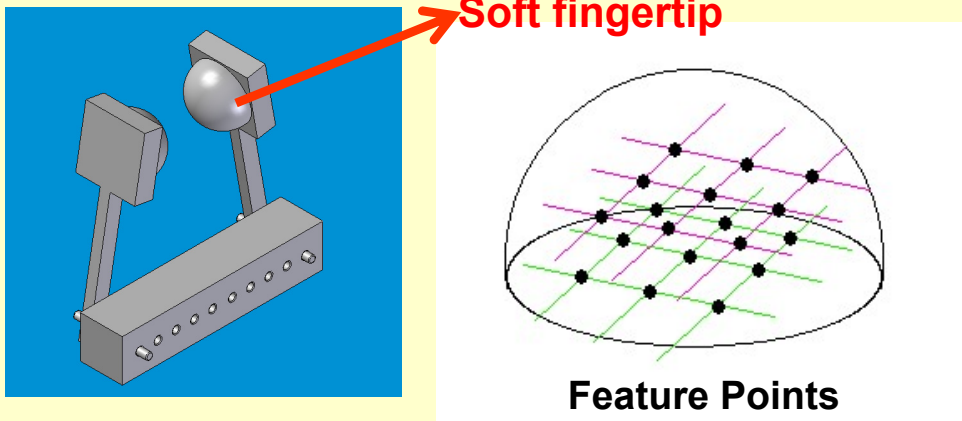
Inner Displacement Measurement of Grasping by Robotic Hand

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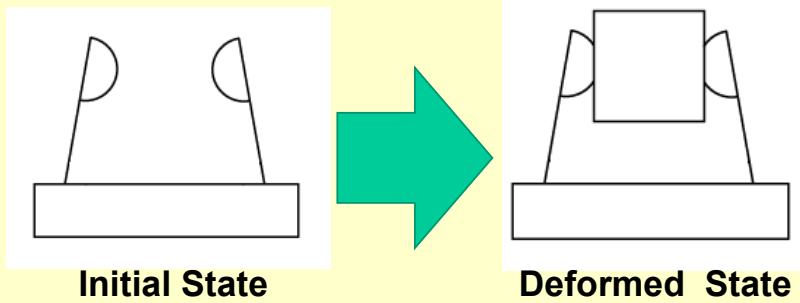
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We measured the inner deformation of soft fingertips of a robotic hand holding a rigid object. We used an MR imager to measure the inner deformation and computed the displacement of feature points. We show experimental setup and result.

Experiment Setup



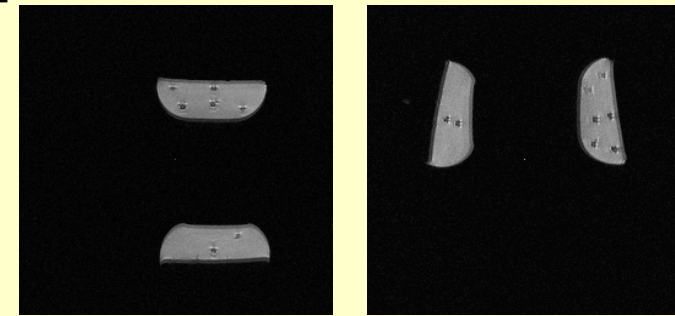
Flexible Hand



Initial State

Deformed State

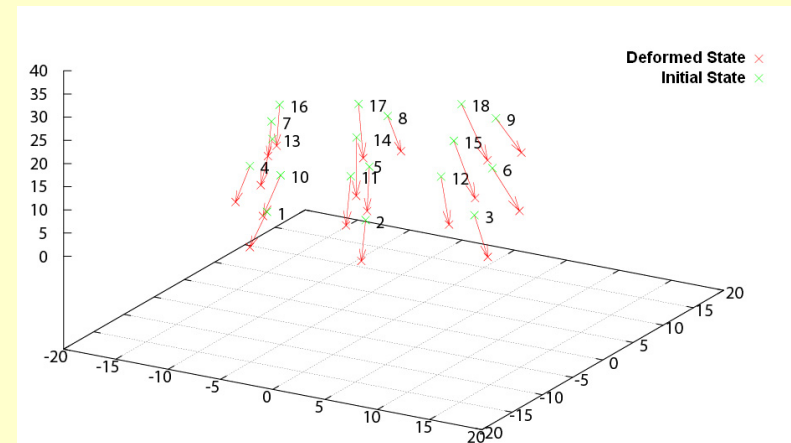
Experiment Result



Coronal

Sagittal

MR images of Deformed Fingertips



Inner Deformation of Fingertips