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**
- **Sagital**

**MR images of Deformed Fingertips**

**Inner Deformation of Fingertips**