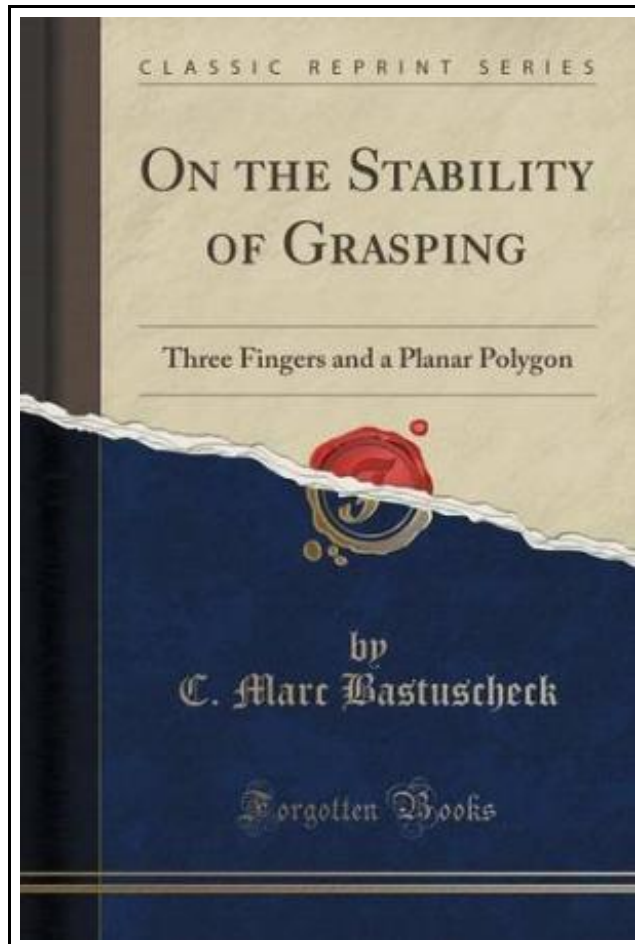


On the Stability of Grasping: Three Fingers and a Planar Polygon (Classic Reprint) (Paperback)



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Reviews

Simply no words to spell out. It can be rally fascinating throgh studying period of time. You will not really feel monotony at at any moment of your own time (that's what catalogues are for concerning if you ask me).

(Dr. Isabella Turner)

ON THE STABILITY OF GRASPING: THREE FINGERS AND A PLANAR POLYGON (CLASSIC REPRINT) (PAPERBACK)



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Forgotten Books, United States, 2015. Paperback. Book Condition: New. 229 x 152 mm. Language: English . Brand New Book ***** Print on Demand *****.Excerpt from On the Stability of Grasping: Three Fingers and a Planar Polygon Grasping an object can be accomplished with very little information about the shape of the object. The approach to a stable grasp is examined carefully for the 2D case of a triangle being grasped by 3 fingers with no effects of friction or mass. The motion of the triangle in contact with two fixed fingers and one moving finger is determined, and a large class of motions is found to result in an equilibrium grasp. The results easily generalize to planar polygons, are expected to extend to real fingers grasping plate-like polygonal objects in the presence of mass and friction. Optimum grasping points for poorly known objects are given as those with the best toleration of error. 1. Introduction The problem of grasp planning is often approached with tacit assumptions that the object to be grasped is perfectly known, and that the end-effector or hand can be positioned with perfect control of force and location of every element in contact with the object. In many robotic applications, however, only a rough idea of object shape and location may be available, e.g. provided by a vision system. It is shown in this paper that uncertain information can be sufficient to ensure successful grasping because an object tends to move towards a more stable configuration under certain grasping conditions. This behavior can be exploited in procedures for initial object acquisition or for pick-and-place operations, since the identity and or orientation of the grasped object can be sensed after acquisition and subsequent robot motion appropriately adjusted. In this paper issues involved in the stable approach to a...

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