



Robotics Research Technical Report: Finding Effective Force-Targets for Two-Dimensional Multifinger Frictional Grips (Classic Reprint)

By Jacob T Schwartz

Forgotten Books, United States, 2015. Paperback. Book Condition: New. 229 x 152 mm. Language: English . Brand New Book ***** Print on Demand *****.Excerpt from Robotics Research Technical Report: Finding Effective Force-Targets for Two-Dimensional Multifinger Frictional Grips In this paper we consider the problem of calculating force targets for a collection of a fingers which grasp a two-dimensional object at known positions, at which the normals to the surface are also assumed to be known at least approximately. If the points at which the fingers touch the body do not allow a positive grip to be exerted (i.e. a grip in which the fingers hold the body in equilibrium by exerting friction-free forces in the directions of the corresponding inward-directed normals), it is appropriate to find the smallest coefficient of friction for which it is possible to assign a set of finger-force targets which hold the object at equilibrium and such that each individual force lies within the corresponding cone of friction. We also present another algorithm for preprocessing the given data so as to allow fast computation of the desired coefficient of friction for the case in which one needs to balance any given query external force and torque....



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