

Mechatronics and Making Mid-Term Project Report Exoskeleton Robotic Hand With Wolf Claw Mechanism

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Contents

1	Introduction	2
1.1	Project Objectives and Description	2
1.2	Similar Mechanisms	2
1.3	Industrial Applications	2
2	Mechanical and Mechanism Analysis	3
2.1	Drive Method and Transmission	3
2.1.1	Transmission Process Details	4
2.2	Fingers and Wrist Mechanisms	4
2.3	Wolf Claw Mechanism Comparison	4
2.3.1	Version 1: Planetary Gear	4
2.3.2	Version 2: Compound Gear Train	4
3	Mathematical Modelling and Analysis	5
3.1	Fingers and Wrist Modelling	5
3.2	Wolf Claw Mechanism Version 1: Planetary Gear	5
3.3	Wolf Claw Mechanism Version 2: Compound Gear Train	5
4	Conclusion and Future Work	6

1 Introduction

1.1 Project Objectives and Description

1.2 Similar Mechanisms

1.3 Industrial Applications

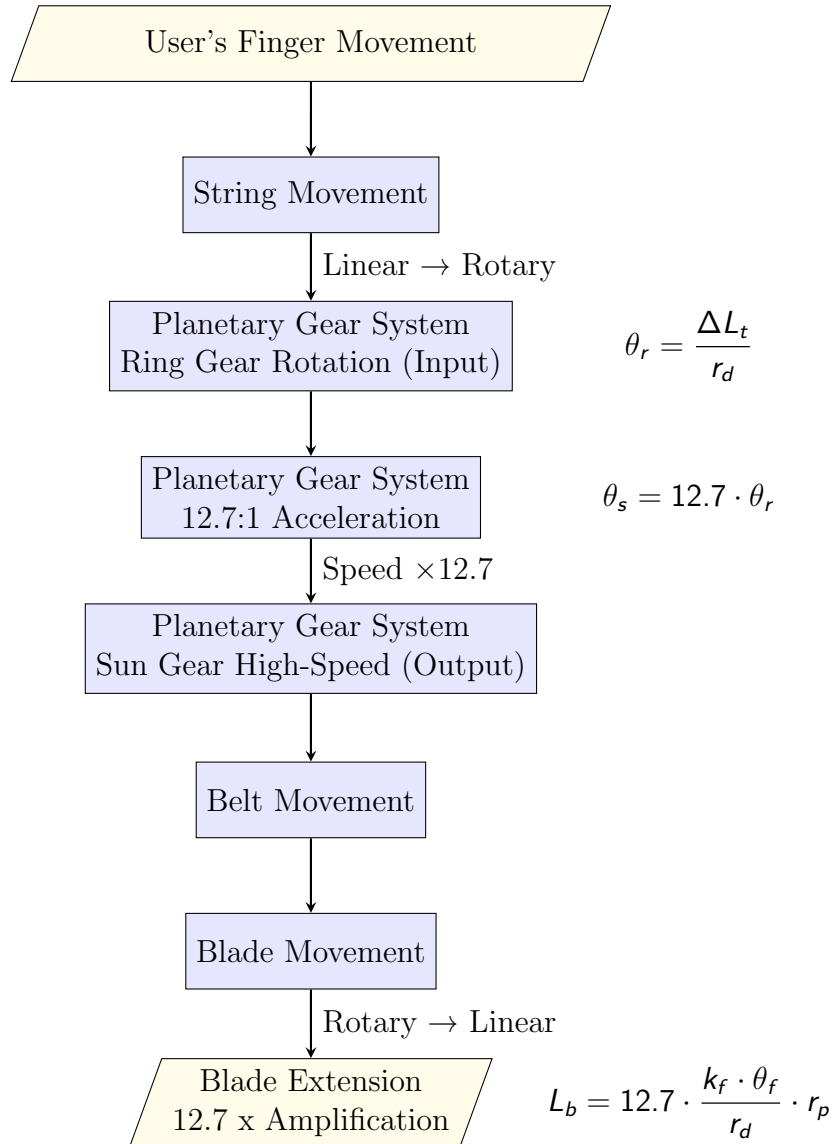
2 Mechanical and Mechanism Analysis

2.1 Drive Method and Transmission

This robotic hand exoskeleton uses an acceleration-based machinery system. Therefore, the movements of the finger will be amplified by this mechanism.

This mechanism can do that through a planetary gear mechanism, whereas a belt system and a string transmission system are also needed.

Details of the transmission process shows below:



2.1.1 Transmission Process Details

User's Input (Finger Movement)

The linear movement of the string that is deployed over the finger is created by the finger's flexion.

Figure 1 has two sub-figures: Figure 1(a) Describe the details and data when finger curved, Figure 1(b) Describe the details and data when finger extended.

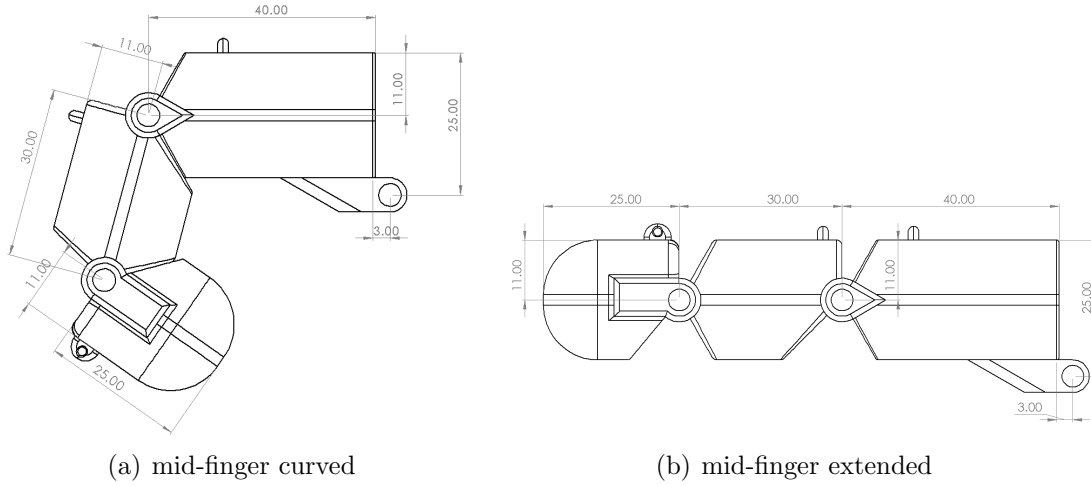


Figure 1: mid-finger exoskeleton design

Total displacement of the string overhead by calculation:¹

$$r = 0P = 0$$

2.2 Fingers and Wrist Mechanisms

2.3 Wolf Claw Mechanism Comparison

2.3.1 Version 1: Planetary Gear

2.3.2 Version 2: Compound Gear Train

3 Mathematical Modelling and Analysis

3.1 Fingers and Wrist Modelling

3.2 Wolf Claw Mechanism Version 1: Planetary Gear

3.3 Wolf Claw Mechanism Version 2: Compound Gear Train

4 Conclusion and Future Work

References

- [1] author. title. In editor, editor, *booktitle*, year.