Aspect/Function	Option 1	Option 2	Option 3	Option 4	Option 5
Mechanical					
EndEffector Type	1DOF Clamping Mechanism	Suction Mechanism	Hook	5 Finger Mechanical Hand	Jamming Mechanism
(Dexterity 1-10, Simplicity 1-5, Durability 1-5)	*(2, 5, 5) = 12*	*(2, 4, 3) = 9*	*(1, 5, 5) = 11*	*(10, 1, 2) = 13*	*(8, 3, 2) = 13*
Driving Mechanism	Direct Motor Drive	Indirect Motor Drive (Lines)	Pneumatic Drive	Hydralic Drive	Air Muscle
(Precision 1-10, Speed 1-10, Torque/Force 1-10, System Size 1-5)	(10, 10, 6, 5) = 31	(10, 10, 6, 4) = 30	(5, 10, 8, 1) = 24	(5, 8, 10, 1) = 24	(5, 10, 7, 3) = 25
Software					
Kinematic Processing	Average PC	Microprocessor	FPGA	Cloud Computing	Analog Electronic Circuits
(Processing Power 1-10, Response Time 1-10,Size 1-10, Cost 1-10)	*(8, 8, 4, 4) = 24*	*(4, 8, 10, 10) = 32*	*(8, 10, 8, 10) = 32*	*(10, 3 10, 8) = 31*	(2, 10, 5, 6) = 23
Sensing					
Endeffector Position Control	Accelometer and Gyroscope	Vision Control	Flex Sensor	Tensometers	Inductive Sensor
(Usability 1-5, Accuracy 1-10, Responsivness 1-10, Cost 1-5)	*(4, 8, 9, 4) = 26*	*(5, 6, 8, 5) = 24*	*(4, 3, 7, 1) = 15*	*(4, 1, 9, 2) = 16*	*(3, 6, 8, 4) = 21*

	Option 6	Option 7	Option 8	Option 9
Mechanical				
EndEffector Type	Precision Probes	Excavater Bucket	Three Fingered Hand	Friction Gripper
(Dexterity 1-10, Simplicity 1-5, Durability 1-5)	*(5, 4, 3) = 12*	*(1, 5, 5) = 11*	*(9, 2, 3) = 14*	*(2, 4, 4) = 10*
Driving Mechanism	Smart material heat responsive	Smart material electric sensitive		
(Precision 1-10, Speed 1-10, Torque/Force 1-10, System Size 1-5)	(3, 2, 4, 5) = 14	(3, 4, 4, 5) = 16		
Software				
Kinematic Processing				
(Processing Power 1-10, Response Time 1-10,Size 1-10, Cost 1-10)				
Sensing				
Endeffector Position Control	Joystick	Keyboards	Artificial Inteligence	Electrodes
(Usability 1-5, Accuracy 1-10, Responsivness 1-10, Cost 1-5)	*(1, 8, 10, 3) = 22*	*(4, 1, 10, 5) = 20*	*(5, 6, 8, 5) = 24*	(5, 10, 10, 5) = 30