

Underactuated robotic hands

Springer - Design and kinematic optimization of a novel underactuated robotic hand exoskeleton



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Mouida A, Alaa N 2011 Sensitivity analysis of TSEB model by One-Factor-At-A-Time in irrigated olive orchard.

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In this case, the operator, after placing the object on the palm 2, commands the motors 54, via the control unit, to exert different torques, and therefore different forces on the cable 53 a condition obtainable by commanding the motors 54 to move in the opposite direction, by imposing the same direction but a different modulus, or by leaving one motor 54 inactive. In summary, the effects resulting from the presence of two motors, which can be controlled by the control unit independently of each other, on the distribution of the tension on the cable 53 entail an actual multiplicity of closure morphologies, and this gives the robotic hand 1 innovative and increased handling capabilities. Google has not performed a legal analysis and makes no representation as to the accuracy of the date listed.

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Advantageously, at least one of the first 51 and second pulleys 52 has a different friction, causing tension drops in the single cable 53, which are different from one another, so that the single cable 53 comprises subtended sectors between the pulleys 51 and 52, which have a non-homogeneous tension, giving different actuation forces to the elements and consequently different mutual rotation speeds between said elements. More in detail, said single cable 53 is arranged to run in all the pulleys 51 and 52 of all the phalanges 3 a and 3 b and, suitably, of the palm 2. It is noted that the elastic means 42, as described in greater detail below, work in opposition to a closure of the hand, i.

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It should be noted that each proximal phalanx 3 a can define, for the axes of the pulleys 51 and 52 therewith associated, its own lying plane 5 a distinct from that of the adjacent phalanx.

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