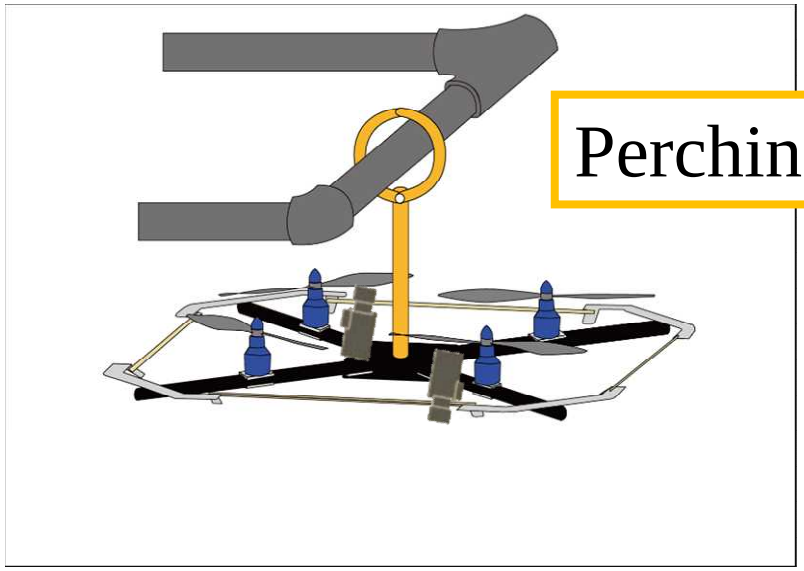
新技術説明会
New Technology Presentation Meetings!

多様な物体を把持する流体圧ロボットハンド

東京工業大学　工学院システム制御系

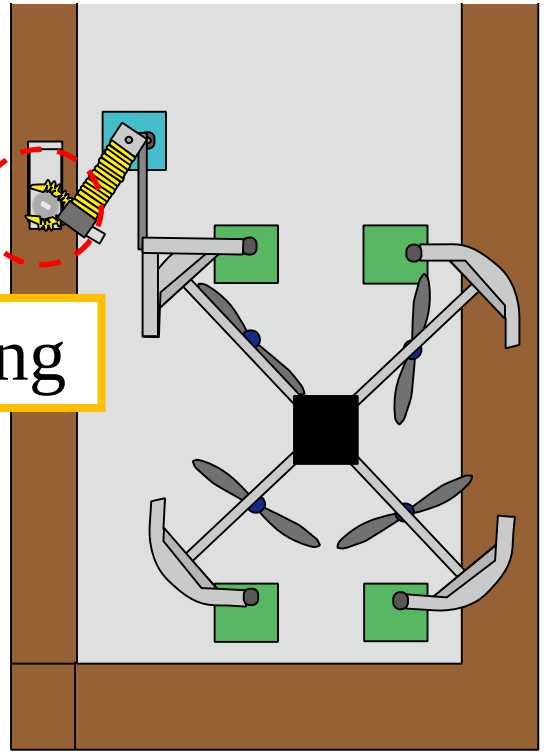
塚越秀行

Effectiveness of grasping function

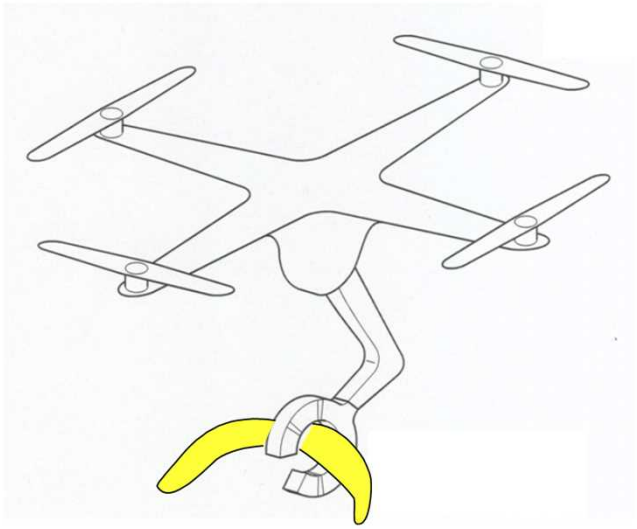


Perching

Handling



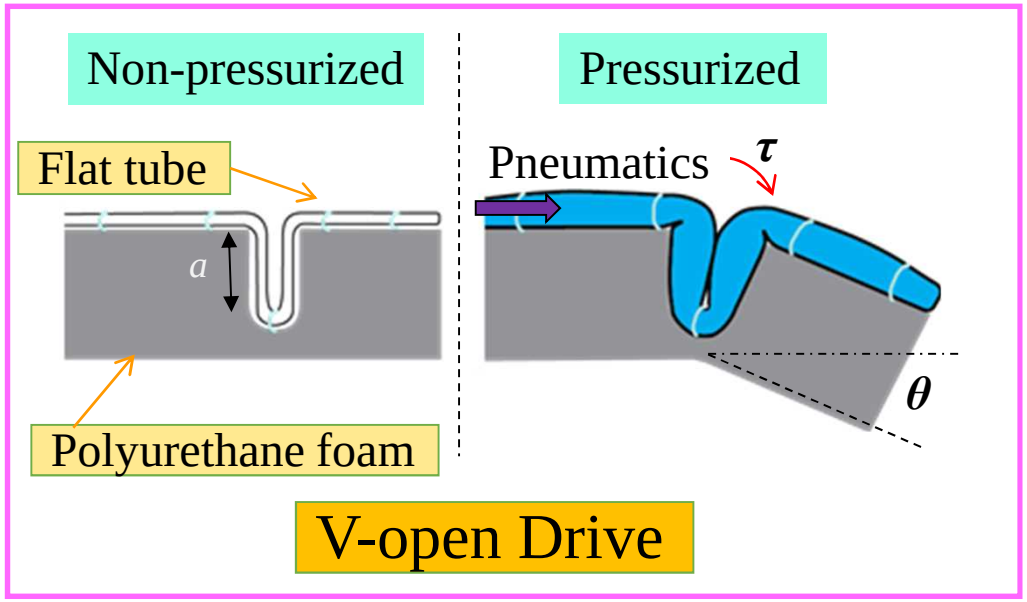
Carrying

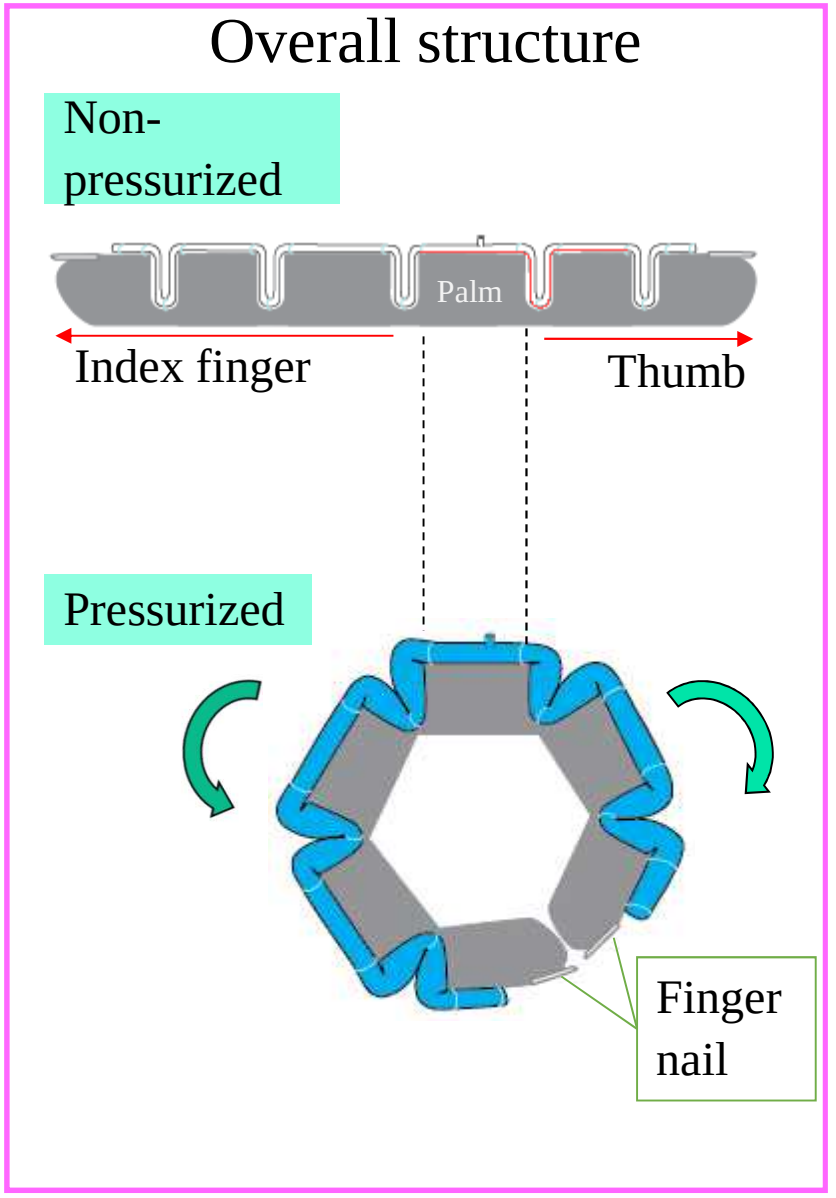


Aerial manipulator with door-opening function

H.Tsukagoshi, M, Watanabe, T.Hamada, D.Ashlih, and R.Iizuka (ICRA2015)

Proposed Finger Structure





Uniformly Distributed Grasping Force

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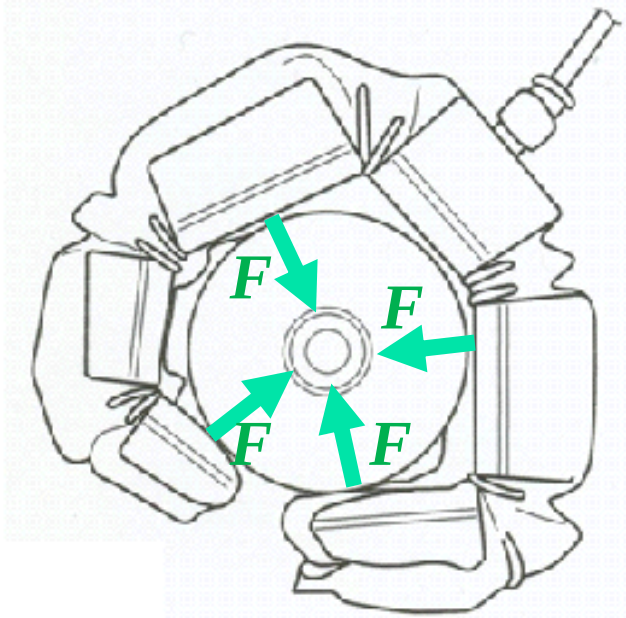

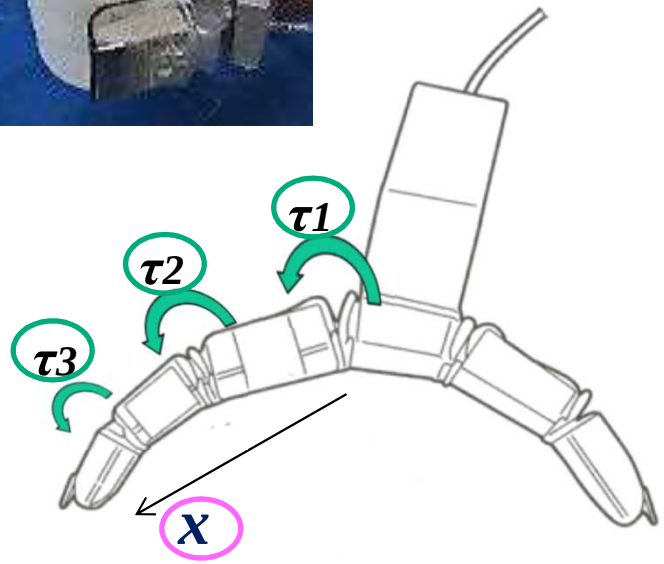

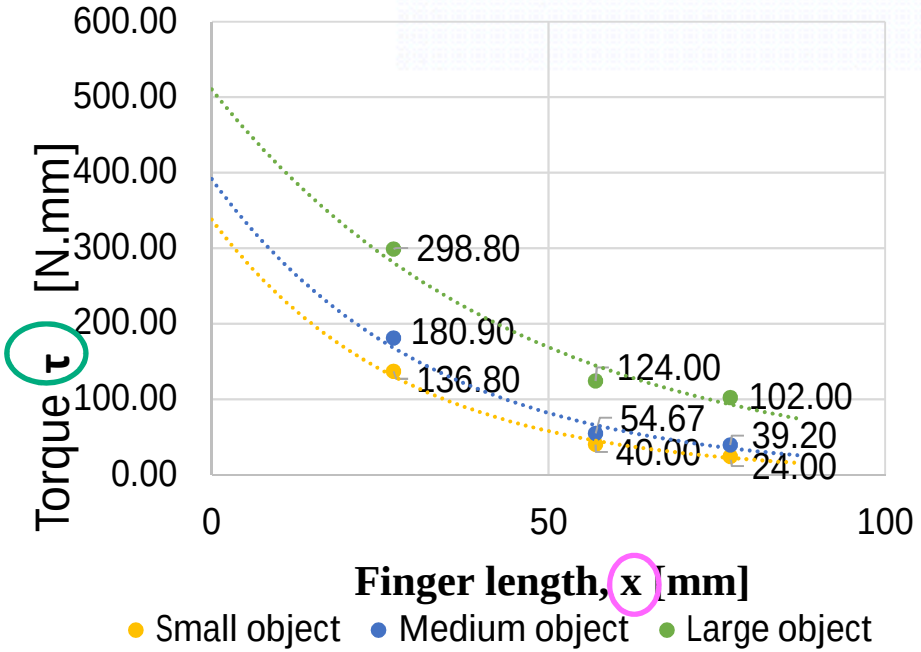

Grasping small and thin objects by nails

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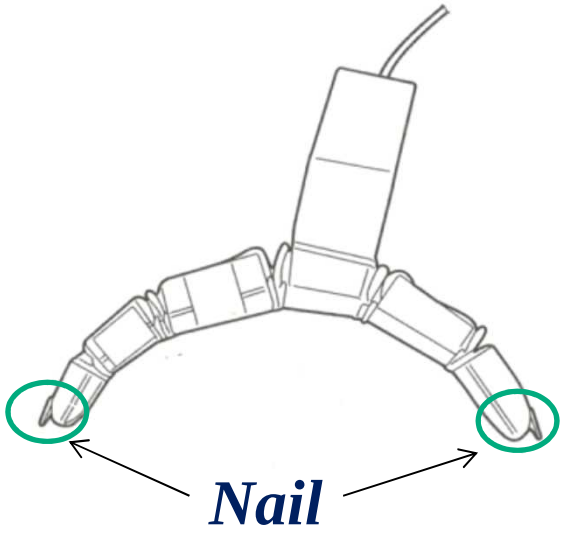
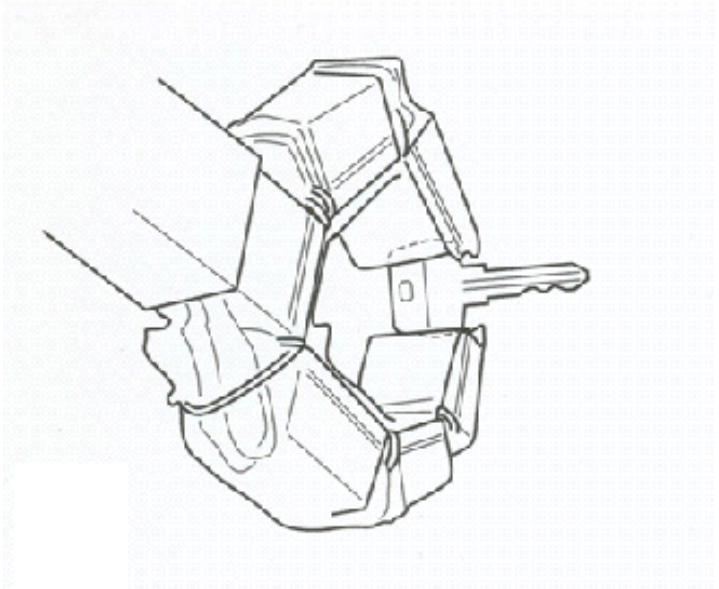
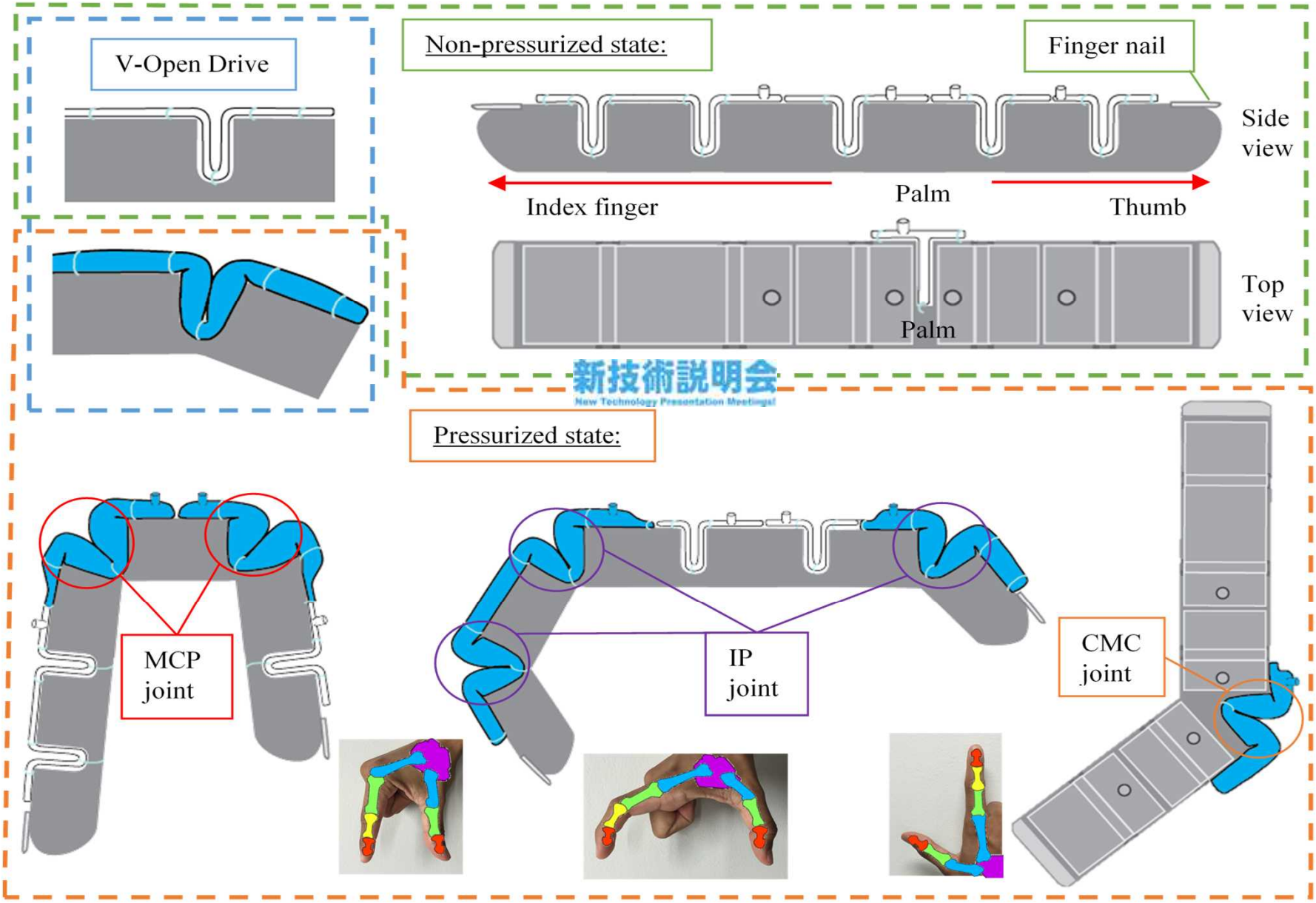




3 DOF Finger Structure



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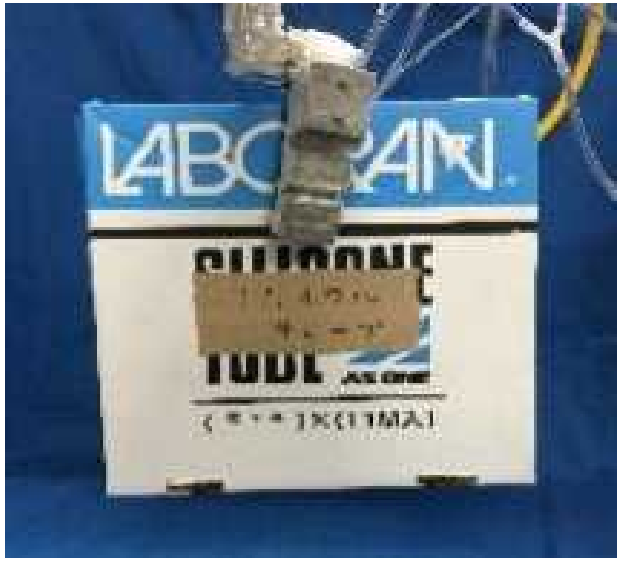
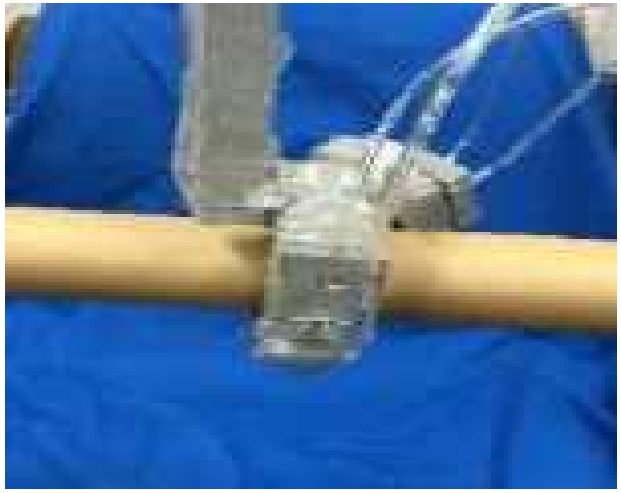
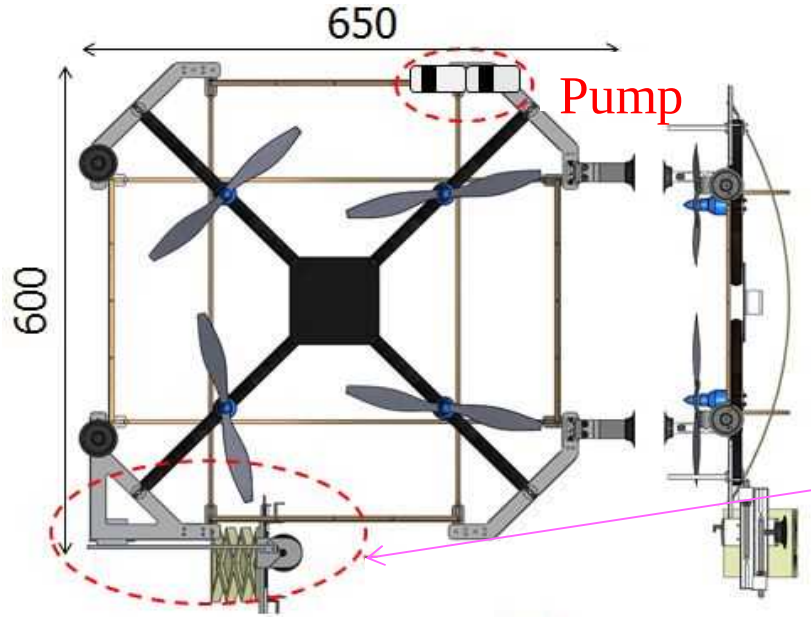
3 DOF Finger Structure

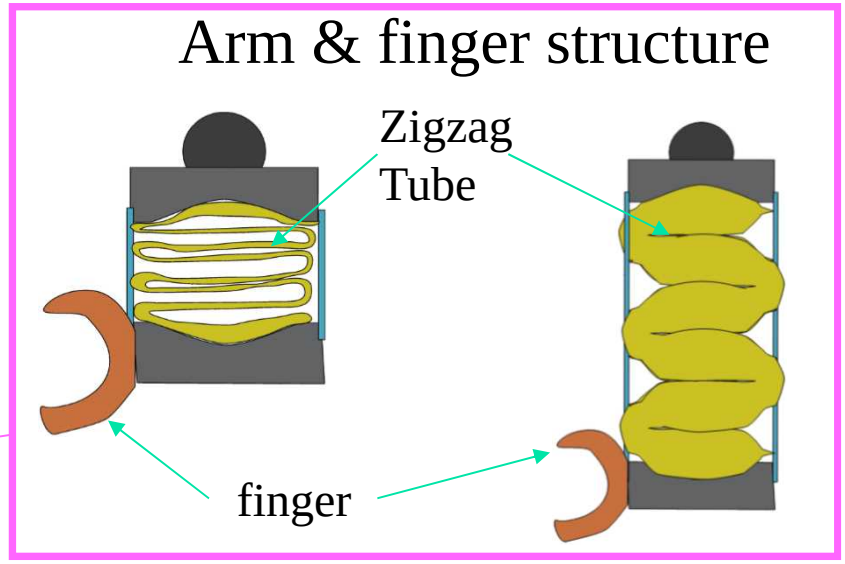




Round knob twisting by the aerial manipulator

Finger Aspect (from index to thumb)	Specification	
	Human Finger	Finger Actuator
Weight	85 gr	32 gr
Length size (flexion-extension)	159-174 mm	163 mm
Width size	14-17 mm	20 mm
Distributed Grasping Force (for door knob)	3 N	5 N
Pressure Input	-	60 – 100 kPa





本技術に関する知的財産権

- 発明の名称　：ロボットハンドおよび飛行ロボット
- 出願番号　　：特願2016-097190
- 出願人　　：東京工業大学
- 発明者　　：塚越秀行、ダメートリ　アシュリ

関連する知的財産権

- 特許4923239　流体アクチュエータ
- 特許5317096　物体把持装置
- 特許5692781　アクチュエータ

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