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I Table Of Contents 1. Introduction 1.1 Previous Investigations On Prehension 1.2 Current Investigation 2.1 Grasping Model And Assumptions 2.2 Stiffness, Strength And Stability Of A Grasp 2.3 I'rocedurc For Establishing Grip Properties 2.4 Two-Dimensional Examples 2.4.1 Choosing Between Five Grips: An Example 2.4.2 An Unstable Example 3. Extension To Three-Dimensional P Jun 1th, 2024

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Material Recognition And Object Manipulation And Can Replace Manual Sorters In The Final Stages Of Waste Sorting. It Can Also Sort Waste Streams That Omit The Initial Energy-consuming Resizing Step (non-destructive Recycling), Because The Robot Can Manipulate Objects Of Varying Sizes And Shapes. Figure 1: ZenRobotics Recycler. 1. Sensors 2. Jun 4th, 2024

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