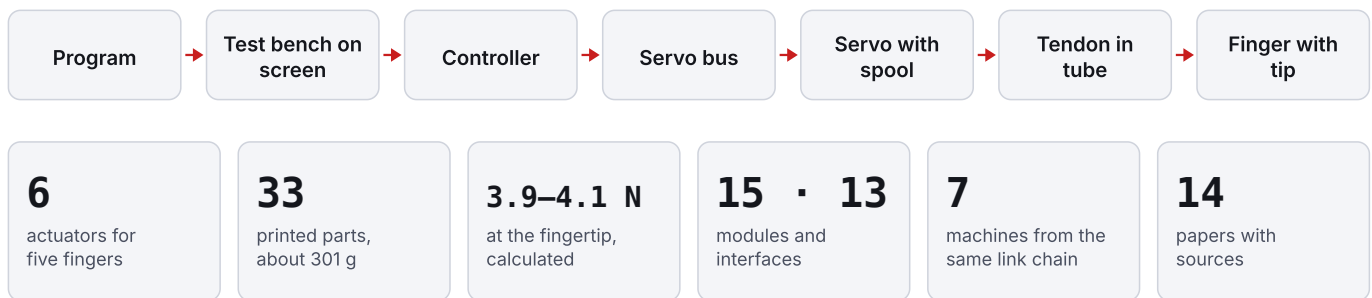


A printed hand that pulls on tendons, as a kit of modules

From calculation model through design, motion program and controller to the teaching pack: one project, one shared description, several partners. Everything is a draft and checked by calculation; nothing has been printed or measured yet.

FROM PROGRAM TO FINGER



STATUS

● Available

Calculator, motion test bench and workshop in the browser
14 papers, manual, module catalogue
7 machines as description and as URDF

● Draft, untested

Hand with fingertips, flange adapter and drive unit
Controller: motion program to commands for bus servos
Teaching pack, eight exercises, training and inspection plans

● Not yet

no part printed, no actuator connected
no value measured; all figures are calculated

NEXT STEPS

- 1 Print the test finger and run five measurement series
- 2 Obtain one servo and take three dimensions from it
- 3 Run one finger through tube and servo, measure force
- 4 Build the hand; try workshop and teaching pack in a trial

WHO CONTRIBUTES WHAT

LEAD AND MANUFACTURING	BUILDS AND EXPERIMENTS	COURSE CATALOGUE AND TEACHING	METHOD AND PUBLICATION
Manufacturing business CONTRIBUTES design, printed parts, kit, contract manufacturing RECEIVES measurements and feedback from experiments and teaching	Experimental platform CONTRIBUTES grid system, test carriers, a home for further machines RECEIVES link chain and chain description	Learning platform CONTRIBUTES catalogue, booking and billing for courses RECEIVES teaching pack and four courses for the catalogue	Independent research CONTRIBUTES measurement method, review, deposit RECEIVES measurement series and profiles of models from nature

LIMITS

Not a medical device: a robot end effector for teaching, experiments and research, not for use on or in the human body.
No work for armaments, the military or weapons.
Disclosure: the project comes from a business that earns money with additive manufacturing.

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