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Ihrke et al.

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(54) **ROBOTIC FINGER ASSEMBLY**

(71) Applicants: **GM Global Technology Operations, Inc.**, Detroit, MI (US); **The United States of America as Represented by the National Aeronautics and Space Administration**, Washington, DC (US)

(72) Inventors: **Chris A. Ihrke**, Hartland, MI (US); **Lyndon Bridgwater**, Houston, TX (US); **Myron A. Diftler**, Houston, TX (US); **Douglas Martin Linn**, White Lake, MI (US); **Robert J. Platt, Jr.**, Houston, TX (US); **Brian Hargrave**, Dickenson, TX (US); **Scott R. Askew**, Houston, TX (US); **Michael C. Valvo**, League City, TX (US)

(73) Assignee: **GM Global Technology Operations LLC**, Detroit, MI (US)

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B25J 15/10 (2006.01)

(52) **U.S. Cl.**

USPC **294/106**; 901/28; 901/31

(58) **Field of Classification Search**

USPC 294/106, 111; 414/5, 7; 623/24, 57, 64; 901/21, 27, 28, 29, 31, 39; 74/490.04, 74/490.05, 490.06

See application file for complete search history.

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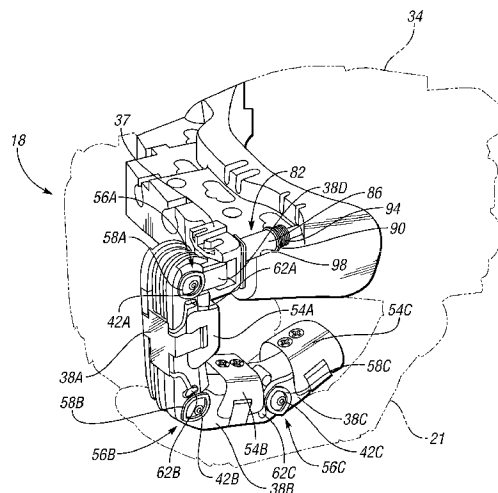
Primary Examiner — Paul T Chin

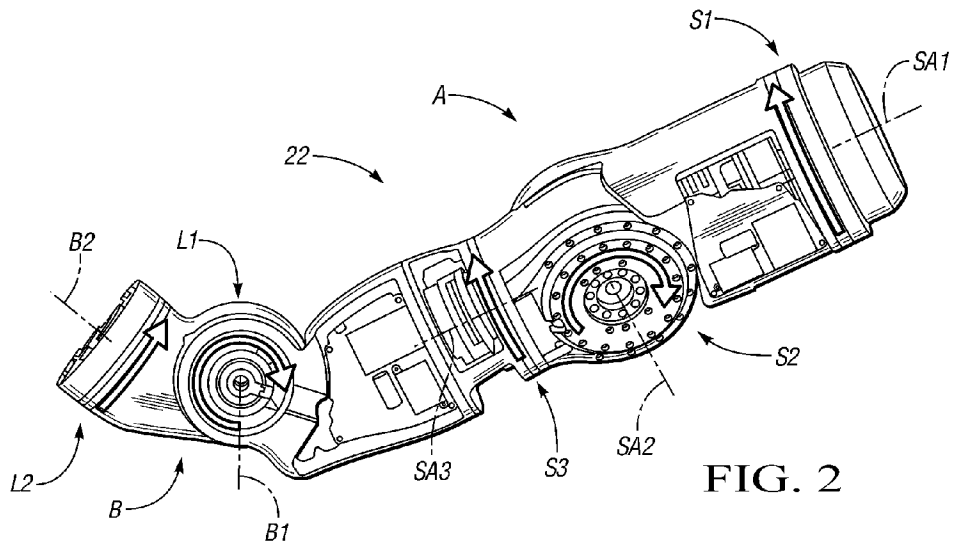
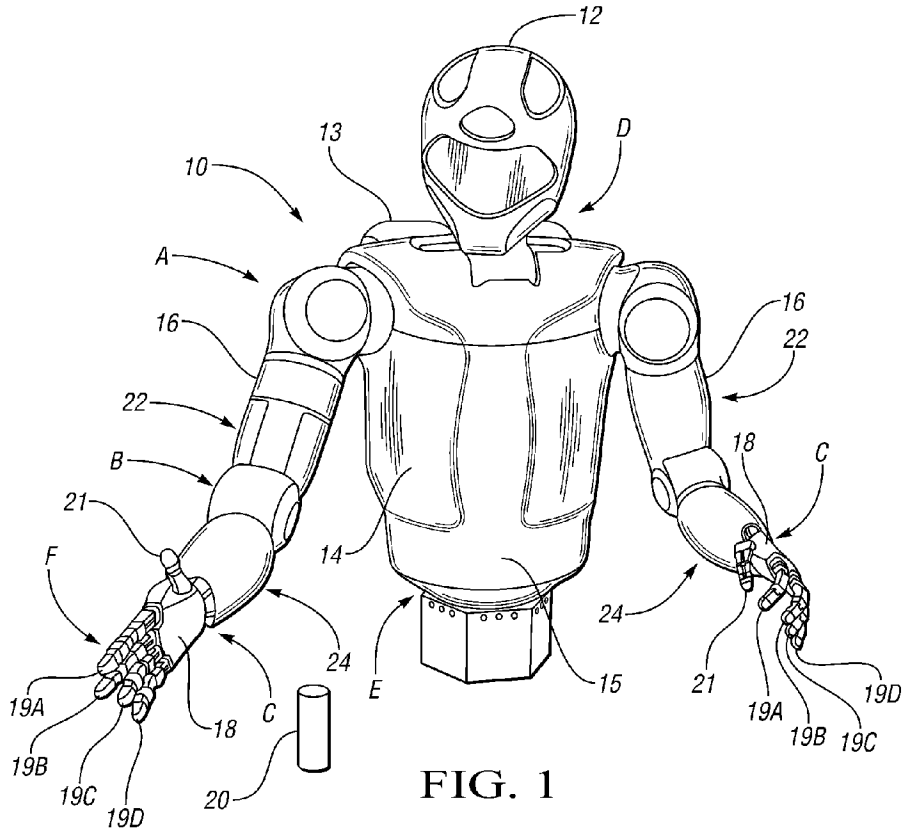
(74) *Attorney, Agent, or Firm* — Quinn Law Group, PLLC

(57) **ABSTRACT**

A robotic hand includes a finger with first, second, and third phalanges. A first joint rotatably connects the first phalange to a base structure. A second joint rotatably connects the first phalange to the second phalange. A third joint rotatably connects the third phalange to the second phalange. The second joint and the third joint are kinematically linked such that the position of the third phalange with respect to the second phalange is determined by the position of the second phalange with respect to the first phalange.

8 Claims, 10 Drawing Sheets





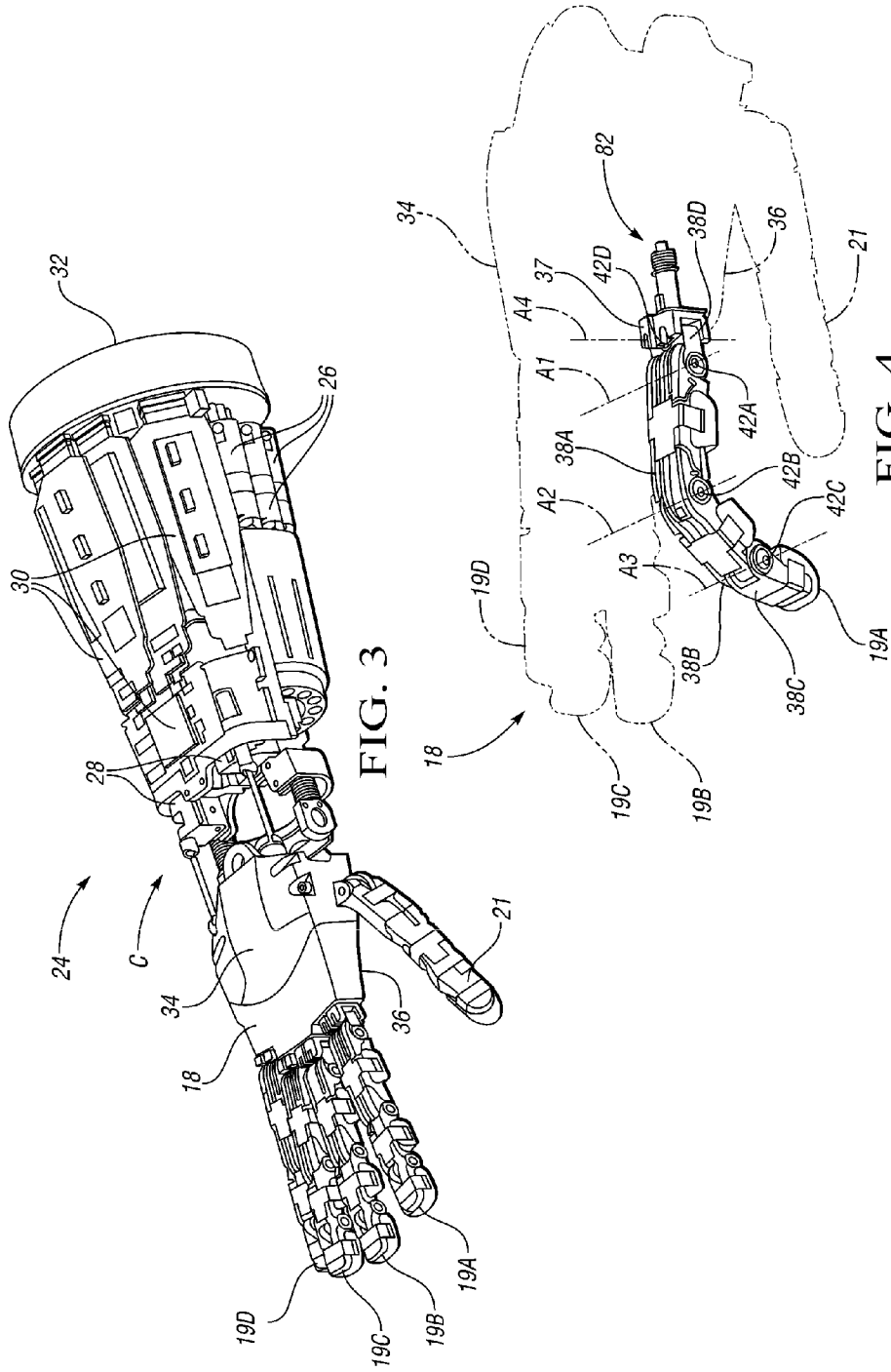


FIG. 3

FIG. 4

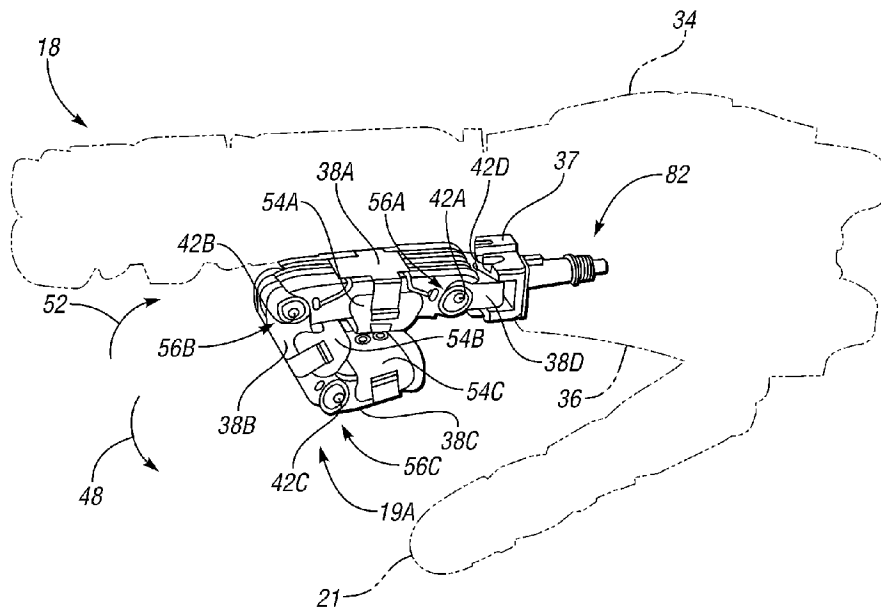


FIG. 5

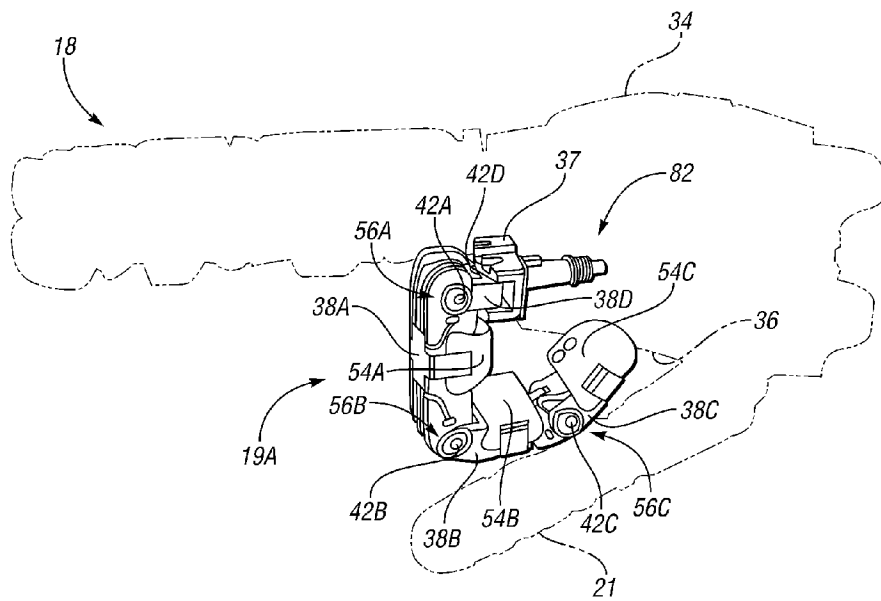


FIG. 6

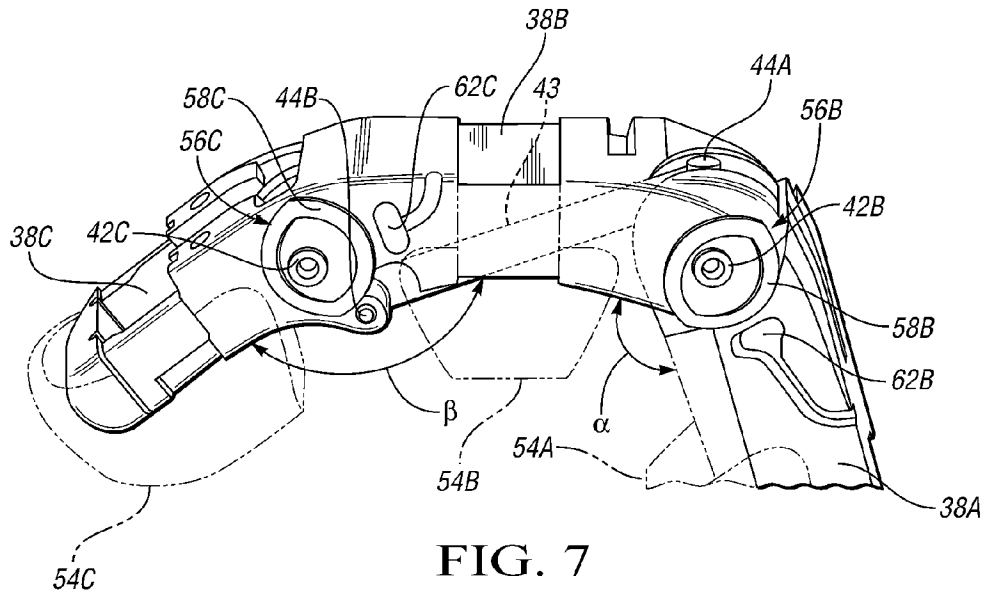


FIG. 7

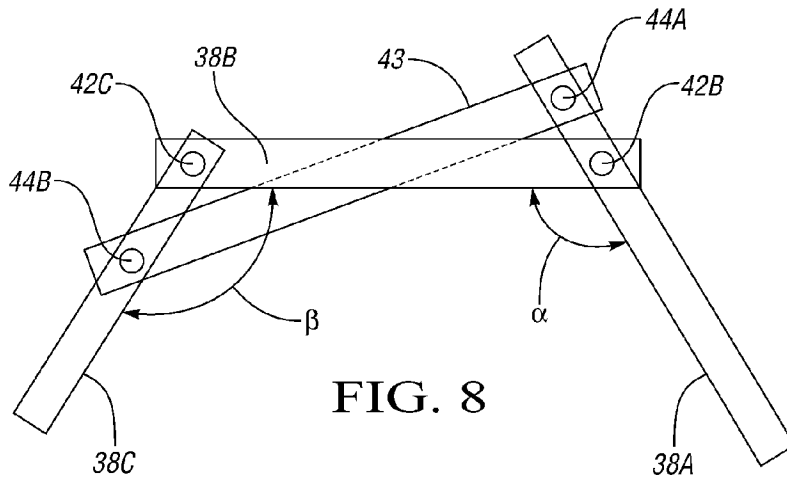


FIG. 8

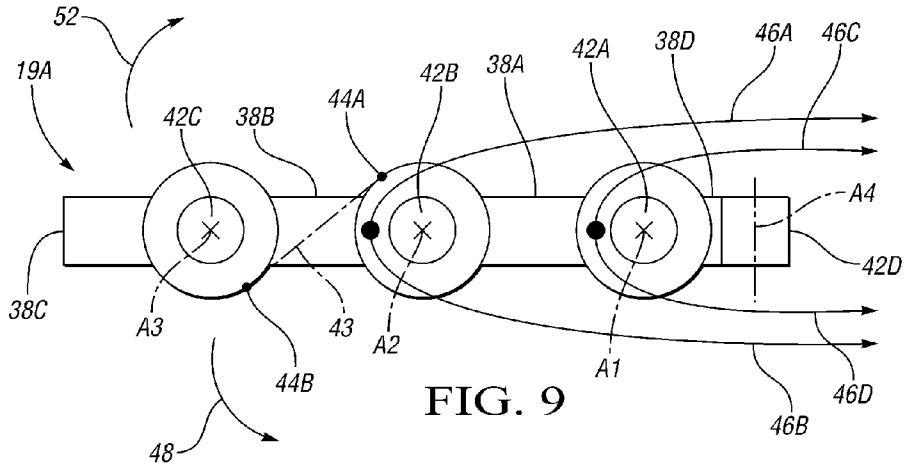


FIG. 9

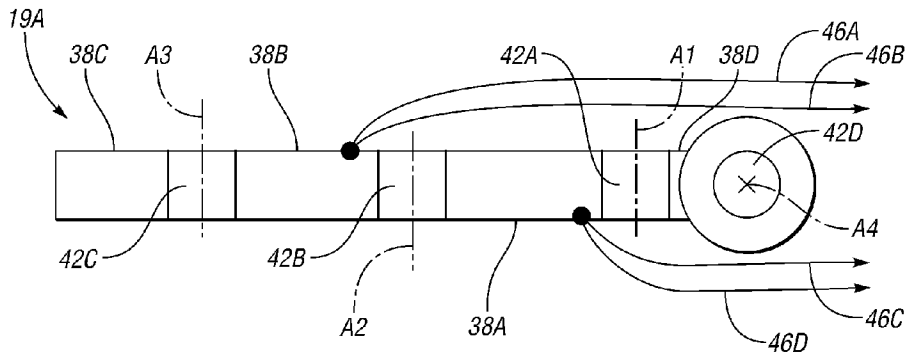


FIG. 11

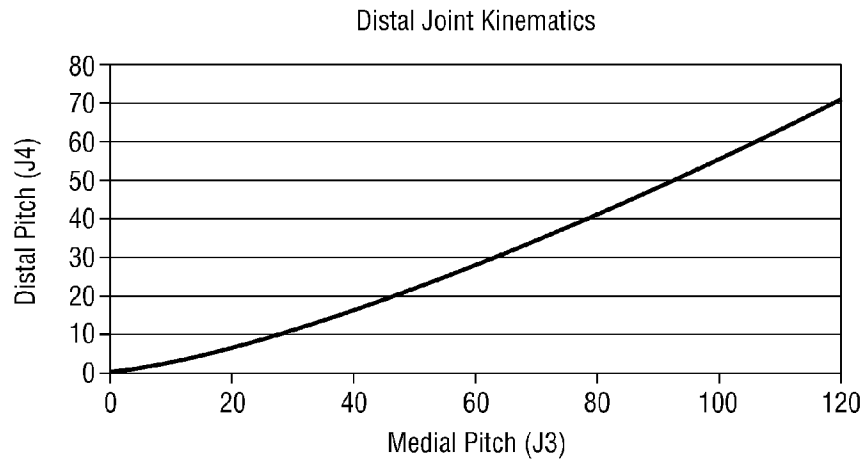


FIG. 10

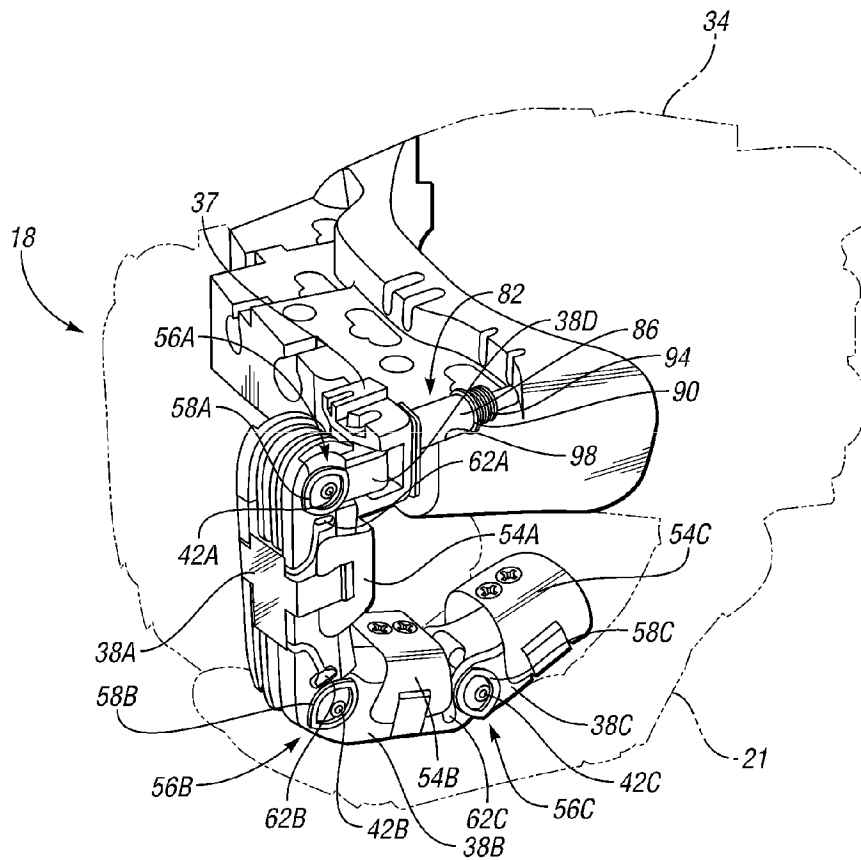


FIG. 12

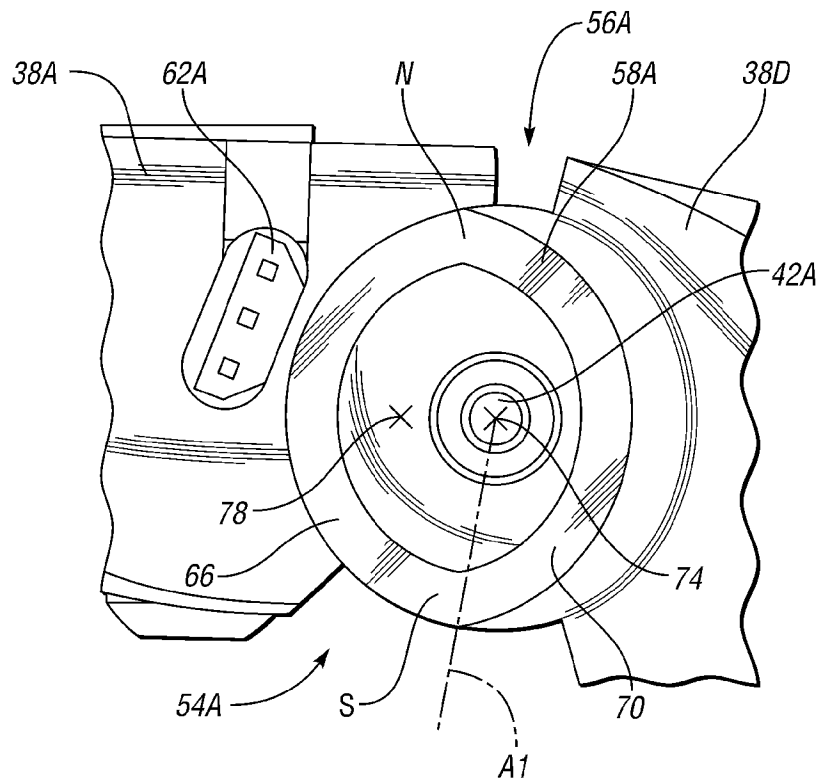


FIG. 13

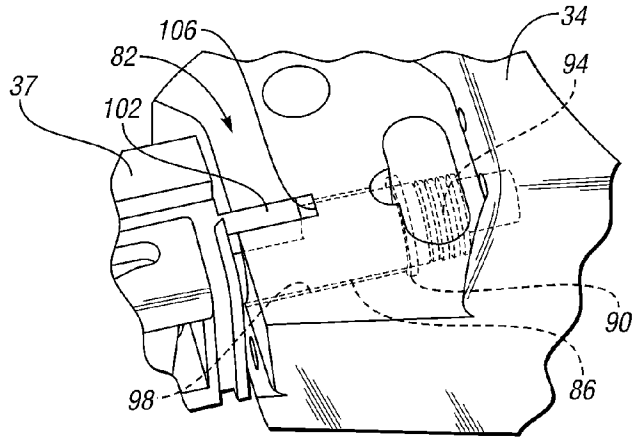


FIG. 14

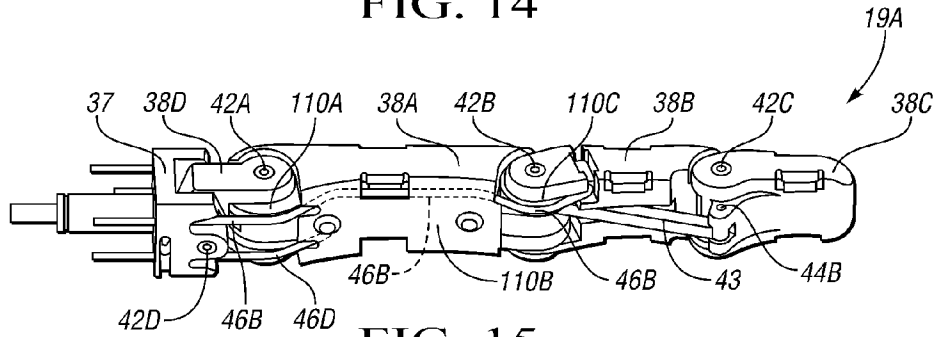


FIG. 15

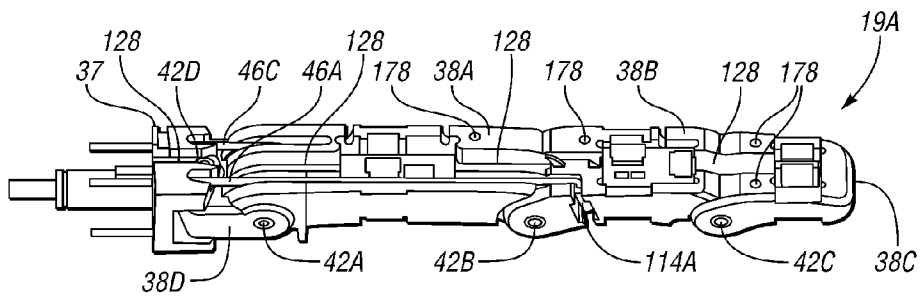


FIG. 16

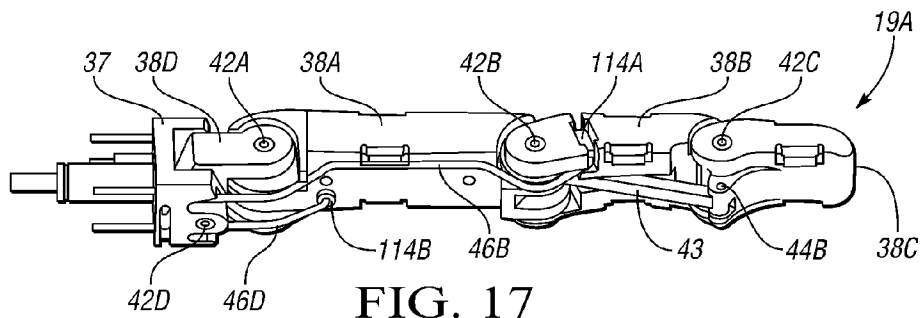


FIG. 17

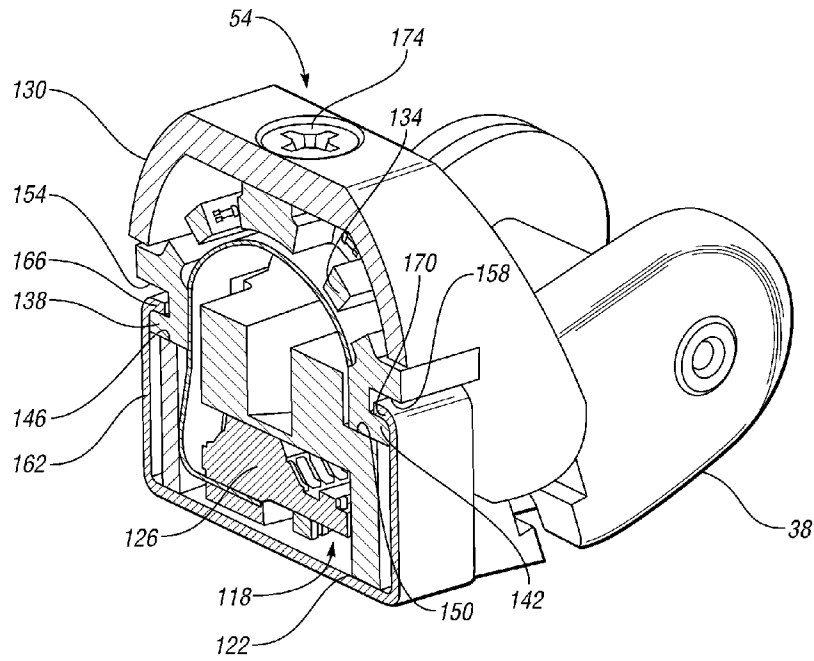


FIG. 18

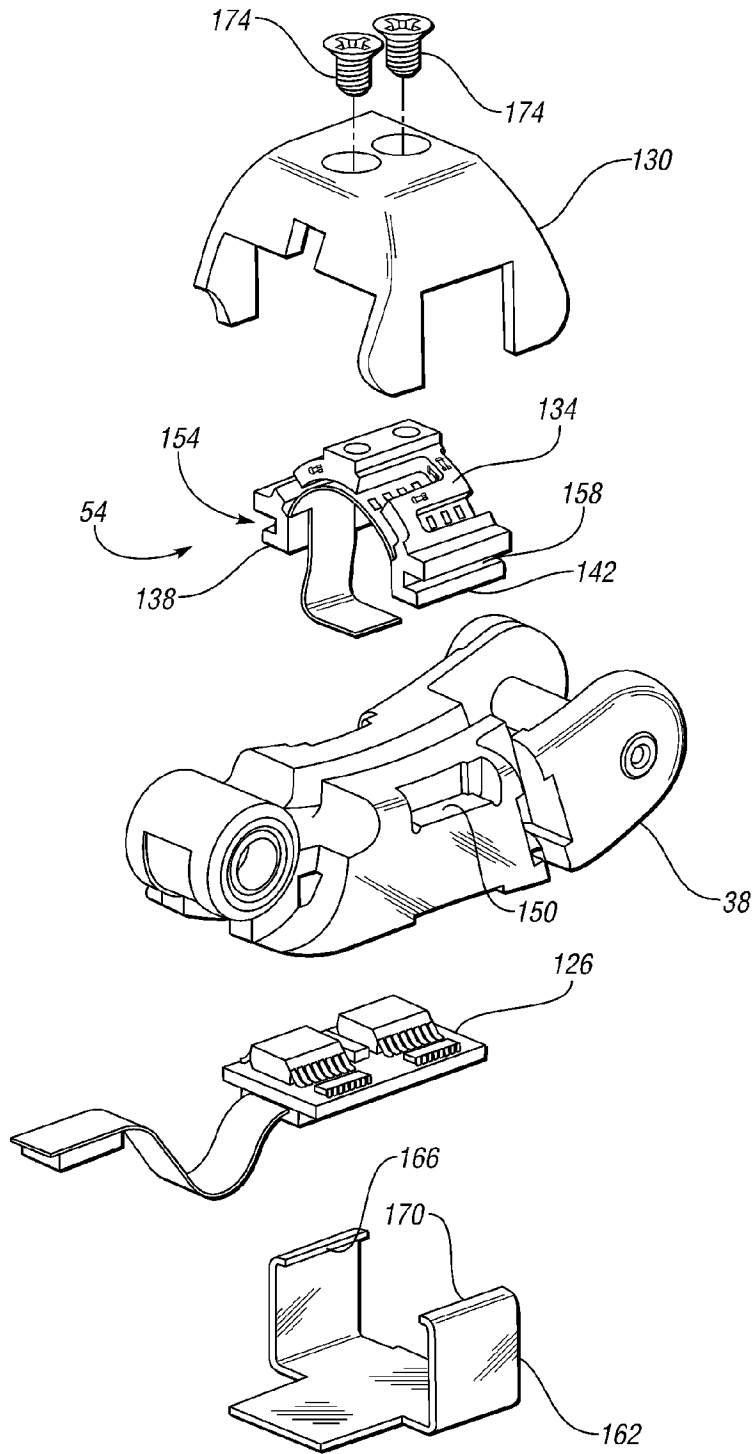


FIG. 19

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ROBOTIC FINGER ASSEMBLY**CROSS-REFERENCE TO RELATED APPLICATION**

This application is a divisional application of U.S. application Ser. No. 12/564,078, filed Sep. 22, 2009, and which is hereby incorporated by reference in its entirety.

STATEMENT REGARDING FEDERALLY SPONSORED RESEARCH OR DEVELOPMENT

This invention was made with government support under NASA Space Act Agreement number SAA-AT-07-003. The government may have certain rights in the invention.

TECHNICAL FIELD

The present invention relates to robotic hands, and more particularly to robotic fingers.

BACKGROUND OF THE INVENTION

Typical robots are automated devices that are able to manipulate objects using a series of rigid links, which in turn are interconnected via articulations or motor-driven robotic joints. Each joint in a typical robot represents an independent control variable, also referred to as a degree of freedom (DOF). End-effectors are the particular links used for performing a task at hand, e.g., grasping a work tool or an object. Therefore, precise motion control of a robot may be organized by the level of task specification: object level control, i.e., the ability to control the behavior of an object held in a single or cooperative grasp of a robot, end-effector control, and joint level control. Collectively, the various control levels cooperate to achieve the required robotic mobility, dexterity, and work task-related functionality.

Humanoid robots in particular are robots having an approximately human structure or appearance, whether a full body, a torso, and/or an appendage, with the structural complexity of the humanoid robot being largely dependent upon the nature of the work task being performed. The use of humanoid robots may be preferred where direct interaction is required with devices or systems that are specifically made for human use. Due to the wide spectrum of work tasks that may be expected of a humanoid robot, different control modes may be simultaneously required. For example, precise control must be applied within the different spaces noted above, as well as control over the applied torque or force, motion, and the various grasp types.

SUMMARY OF THE INVENTION

A robotic hand assembly includes a base structure; a finger having first, second, and third phalanges; a first joint operatively connecting the first phalange to the base structure such that the first phalange is selectively rotatable with respect to the base structure about a first axis; a second joint operatively connecting the second phalange to the first phalange such that the second phalange is selectively rotatable with respect to the first phalange about a second axis; and a third joint operatively connecting the third phalange to the second phalange such that the third phalange is selectively rotatable with respect to the second phalange about a third axis.

The third joint is kinematically linked to the second joint such that the position of the third phalange with respect to the second phalange is determined by the position of the second

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phalange with respect to the first phalange. The kinematic linkage between the second and third joints replaces one of the degrees of freedom of a human finger while closely approximating the movement of a human finger.

The above features and advantages and other features and advantages of the present invention are readily apparent from the following detailed description of the best modes for carrying out the invention when taken in connection with the accompanying drawings.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 is a schematic perspective illustration of a dexterous humanoid robot having two hands;

FIG. 2 is a schematic perspective illustration of an upper arm for the dexterous humanoid robot of FIG. 1;

FIG. 3 is a schematic perspective illustration of a lower arm for the dexterous humanoid robot of FIGS. 1 and 2;

FIG. 4 is a schematic, perspective view of a finger of one of the hands of FIG. 1 in a first position;

FIG. 5 is a schematic, perspective view of the finger of FIG. 4 in a second position; and

FIG. 6 is a schematic, perspective view of the finger of FIGS. 4 and 5 in a third position;

FIG. 7 is a schematic, side view of a portion of the finger of FIG. 4;

FIG. 8 is another schematic, side view of the portion of the finger of FIG. 7;

FIG. 9 is a schematic, side view of the finger of FIG. 4 depicting tendon routing;

FIG. 10 is a graph depicting the position of one of the joints in the finger as a function of the position of another one of the joints in the finger;

FIG. 11 is a schematic, top view of the thumb of FIG. 4 depicting tendon routing;

FIG. 12 is a schematic, perspective view of the finger of FIG. 4 mounted to base structure by a shock mount;

FIG. 13 is a schematic, side view of a sensor assembly at a joint of the finger of FIG. 4;

FIG. 14 is a schematic, perspective view of the shock mount of FIG. 12;

FIG. 15 is another schematic, perspective view of the finger of FIG. 4;

FIG. 16 is yet another schematic, perspective view of the finger of FIG. 4;

FIG. 17 is yet another schematic, perspective view of the finger of FIG. 4;

FIG. 18 is a schematic, perspective, cutaway view of a phalange and sensor assembly that is representative of the phalanges of the finger of FIG. 4; and

FIG. 19 is a schematic, exploded view of the phalange and sensor assembly of FIG. 18.

DESCRIPTION OF THE PREFERRED EMBODIMENT

With reference to the drawings, wherein like reference numbers refer to the same or similar components throughout the several views, FIG. 1 shows a dexterous humanoid robot 10 adapted to perform one or more tasks with multiple degrees of freedom (DOF).

The humanoid robot 10 may include a head 12, torso 14, waist 15, arms 16, hands 18, fingers 19A-19D, and thumbs 21, with various joints being disposed within or therebetween. The robot 10 may also include a task-suitable fixture or base (not shown) such as legs, treads, or another moveable or fixed base depending on the particular application or intended

use of the robot. A power supply **13** may be integrally mounted to the robot **10**, e.g., a rechargeable battery pack carried or worn on the back of the torso **14** or another suitable energy supply.

According to one embodiment, the robot **10** is configured with a plurality of independently and interdependently-moveable robotic joints, such as but not limited to a shoulder joint assembly (arrow A), an elbow joint assembly (arrow B), a wrist joint assembly (arrow C), a neck joint assembly (arrow D), and a waist joint assembly (arrow E), as well as the various finger and thumb joint assemblies (arrow F) positioned between the phalanges of each robotic finger **19A-19D** and thumb **21**.

The arm **16** is divided into an upper arm **22** and a lower arm (or forearm) **24**. The upper arm **22** extends from the shoulder joint assembly (arrow A) to the elbow joint assembly (arrow B). Extending from the elbow joint (arrow B) is the lower arm **24**, hands **18**, fingers **19**, and thumbs **21**. For the purpose of simplification, as described herein, the upward direction is toward the head **12** and the downward direction is toward the waist **15**. Those skilled in the art will appreciate that since the robot **10** is intended to simulate a humanoid, the robot will be substantially symmetrical about a vertical plane bisecting the torso and head, and essentially include an identical symmetrical structure on both the left and right sides.

Referring to FIG. 2, the upper arm **22** is illustrated. Although only one upper arm **22** for the arms **16** is shown, both the left and the right arms **16** operate in the same manner as described below. The upper arm **22** has a shoulder joint assembly (arrow A) that includes a first shoulder joint **S1** providing a first DOF, and second shoulder joint **S2** providing a second DOF, and a third shoulder joint **S3** providing a third degree of freedom. Together the first through third shoulder joints **S1**, **S2**, **S3** perform the movements that represent the movements a human shoulder can perform. Specifically, rotation of the first shoulder joint **S1** about a first shoulder axis **SA1** moves a second shoulder axis **SA2** for the second shoulder joint **S2** into a desired position. Based upon the position of the first shoulder joint **S1**, rotation of the second shoulder joint **S2** about the second shoulder axis **SA2** then moves the arm **16** up and down relative to the torso **14**, or forward and backward relative to the torso **14**. The third shoulder joint **S3** rotates the upper arm **22** about a third shoulder axis **SA3**. Rotation of the third shoulder joint **S3** rotates the upper arm **22** axially, i.e. rotation of the third shoulder joint **S3** rotates the elbow joint assembly (arrow B) to face upwards or downwards. Therefore, together the first shoulder joint **S1**, the second shoulder joint **S2**, and the third shoulder joint **S3** form the motions of a shoulder joint assembly (arrow A).

The upper arm **22** also includes an elbow joint assembly (arrow B) which includes a first elbow joint **L1** and a second elbow joint **L2**. The first elbow joint **L1** and second elbow joint **L2** each provide a degree of freedom. Together the first elbow joint **L1**, and the second elbow joint **L2** perform the movements that represent the movements a human elbow can perform. Rotation of the first elbow joint **L1** about a first elbow axis **B1** causes the upper arm **22**, below the elbow joint assembly (arrow B) to bend and straighten. Additionally, rotation of the second elbow joint **L2** about a second elbow axis **B2** causes the upper arm **22**, below the elbow joint assembly (arrow B) to rotate axially, i.e. rotation of the second elbow joint **L2** about the second elbow axis **B2** rotates the lower arm **24** and hand **18** (FIG. 1) to face palm up or down.

FIG. 3 illustrates the lower arm **24**, including the wrist joint assembly (arrow C), the hand **18**, the fingers **19A-19D**, and thumb **21**. The lower arm **24** includes a plurality of finger (and thumb) actuators **26** and a plurality of wrist actuators **28**.

Additionally, a plurality of controls **30** for the finger actuators **26** and the wrist actuators **28** are also supported on the lower arm **24**. The lower arm **24** is attached to a load cell **32** which is used to connect the lower arm **24** with the upper arm **22**. The hand **18** includes a base structure **34** that defines the palm **36** of the hand **18**. Fingers **19A-19D** and thumb **21** are movably mounted to the base structure **34** and selectively curl toward the palm **36** in order to grip an object, such as the one shown at **20** in FIG. 1.

In the embodiment depicted, the hand **18** is comparable in size to that of a sixtieth to eight-fifth percentile human male hand. More specifically, in the embodiment depicted, the length of the hand **18** is 7.9 inches (eightieth percentile human); the breadth, or width, of the hand **18** is 3.6 inches (sixtieth percentile human); and the circumference of the hand (around the base structure) is 8.8 inches (eighty-fifth percentile human).

Referring to FIGS. 4-7, finger **19A** corresponds in position and function to a human index finger. Finger **19A** includes a base member **37** operatively connected to the base structure **34** of the hand **18**. The finger **19A** also includes a plurality of rigid links, or phalanges **38A-38D**, and four joints **42A-42D**. Joint **42A** operatively connects proximal phalange **38A** to the base structure **34** such that the phalange **38A** is selectively rotatable with respect to the structure **34** about axis **A1**. Joint **42B** rotatably mounts phalange **38B** to phalange **38A** such that phalange **38B** is selectively rotatable with respect to phalange **38A** about axis **A2**. Joint **42C** rotatably mounts phalange **38C** to phalange **38B** such that phalange **38C** is selectively rotatable with respect to phalange **38B** about axis **A3**. Axes **A1**, **A2**, and **A3** are parallel to one another.

In the embodiment depicted, the proximal phalange **38A** is operatively connected to the base structure **34** by phalange **38D**, joint **42D**, and base member **37**. More specifically, joint **42A** rotatably mounts phalange **38A** to phalange **38D**; joint **42D** rotatably mounts phalange **38D** to the base member **37** such that phalange **38D**, and, correspondingly, phalanges **38A-38C**, are selectively rotatable with respect to the base member **37** and the base structure **34** about axis **A4**. Axis **A4** is perpendicular to axes **A1**, **A2**, and **A3**. Thus, joint **42D** permits rotation of the finger **19A** to the right and left.

Referring to FIGS. 7-8, the finger **19A** includes a linkage **43**. One end of the linkage **43** is rotatably connected to phalange **38A** by joint **44A** such that the linkage **43** is selectively rotatable with respect to phalange **38A** about an axis that is parallel to axes **A1**, **A2**, and **A3**. The other end of the linkage **43** is rotatably connected to phalange **38C** by joint **44B** such that the linkage **43** is selectively rotatable with respect to phalange **38C** about an axis that is parallel to axes **A1**, **A2**, and **A3**. Accordingly, phalanges **38A-38C** and linkage **43** cooperate to define a four-bar linkage.

Referring to FIG. 9, wherein like reference numbers refer to like components from FIGS. 1-8, movement of the phalanges **38A-38D** about joints **42A-42D** is accomplished by robotic tendons **46A-46D**, i.e., flexible members such as cables. Each of the tendons **46A-46D** is operatively connected to a respective actuator (shown at **26** in FIG. 3) in the forearm (shown at **24** in FIG. 3). In an exemplary embodiment, the actuators **26** are electric motors operatively connected to the tendons **46A-46D** by drive mechanisms configured to convert the rotary motion of the motors to linear motion to drive the tendons **46A-46D**. The placement of the actuators and drive mechanisms in the forearm **24** and/or wrist contributes to the compactness of the hand **18**.

The routing of the tendons **46A-46D** with respect to the joints **42A-D** and the axes **A1-A4** enables the finger **19A** to be fully controlled through three degrees of freedom using only

the four tendons 46A-46D. Two opposing tendons 46A, 46B control the medial pitch joint 42B, and two opposing tendons 46C, 46D control the proximal pitch joint 42A. One end of tendon 46B is operatively connected to phalange 38B on one side of joint 42B and axis A2 such that tension in tendon 46B causes rotation of phalange 38B with respect to phalange 38A about axis A2 in a first direction 48. One end of tendon 46A is operatively connected to phalange 38B on the opposite side of joint 42B and axis A2 from tendon 46B such that tension in tendon 46A causes rotation of phalange 38B with respect to phalange 38A about axis A2 in a second direction 52 opposite the first direction 48.

One end of tendon 46D is operatively connected to phalange 38A on one side of joint 42A and axis A1 such that tension in tendon 46D causes rotation of phalange 38A with respect to phalange 38D about axis A1 in the first direction 48. One end of tendon 46C is operatively connected to phalange 38A on the opposite side of joint 42A and axis A1 from tendon 46D such that tension in tendon 46C causes rotation of phalange 38A with respect to phalange 38D about axis A1 in the second direction 52. Rotation of the phalanges in the first direction 48 causes the phalanges to rotate toward the palm 36, as shown in FIGS. 5-6, and thus rotation of the phalanges in the first direction 48 enables the hand 18 to grip an object. Rotation of the phalanges in the second direction 52 causes the phalanges to rotate away from the palm 36, and thus causes the finger 19A to release a grip on the object.

Referring again to FIGS. 7-8, joint 42C is kinematically linked to joint 42B via linkage 43, and thus the angular position of joint 42C is dependent upon the angular position of joint 42B. Accordingly, the rotational position of phalange 38C with respect to phalange 38B is dependent upon the rotational position of phalange 38B with respect to phalange 38A. More specifically, the angle β formed between phalanges 38C and 38B is determined by the angle α formed between phalanges 38B and 38A: decreasing α causes a corresponding decrease in β . An exemplary relationship between the rotational position of joint 42C and joint 42B is depicted in FIG. 10.

Referring to FIG. 10, the angle of joint 42C is shown as a function of the angle of joint 42B. It may be desirable for the function to be as linear as the design constraints of the finger 19A will allow. The four bar linkage comprising phalanges 38A-38C and linkage 43 is designed such that the linkage 43 is a straight line member between its end shafts, and is in tension during grasping. Linkage 43 in one embodiment is a rigid member; in another embodiment, linkage 43 is a compliant member, such as a spring, to achieve compliance of the distal pitch joint 42C during grasping.

Accordingly, tendons 46A and 46B control the position of joint 42C via their control of joint 42B. A human finger is generally considered to have four independently controllable degrees of freedom. By kinematically linking joints 42B and 42C, finger 19A effectively approximates the poses achievable by a human finger with only three independently controllable degrees of freedom, thereby eliminating the tendons that would be required to control joint 42D independently.

Referring to FIG. 11, wherein like reference numbers refer to like components from FIGS. 1-11, there are no tendons dedicated to controlling the position of the yaw joint 42D. Instead, tendons 46A and 46B are routed on one side of joint 42D and axis A4, and tendons 46C and 46D are routed on another side of joint 42D and axis A4. The balance of tension in these four tendons 46A-46D is manipulated to control the position of joint 42D and, correspondingly, the angular position of phalanges 38A-38D with respect to the base structure 34.

Referring to FIG. 12, the finger 19A includes at least two types of sensors. More specifically, the sensors of the finger 19A include tactile load cells 54A-54C, each of which is mounted to a respective phalange 38A-38C. The finger 19A also includes a plurality of joint position sensor assemblies 56A-56C, each of which is configured to measure the absolute angular position of a respective one of the joints 42A-42C and the relative angular position of a phalange relative to a connecting phalange. Each of the joint position sensor assemblies 56A-56C includes a respective magnet 58A-58C and a respective Hall effect sensor 62A-62C.

Referring to FIG. 13, sensor assembly 56A is representative of sensor assemblies 56B and 56C, and thus magnet 58A and sensor 62A are representative of magnets 58B, 58C and sensors 62B, 62C, respectively. Magnet 58A is rigidly mounted with respect to phalange 38D, and sensor 62A is rigidly mounted with respect to phalange 38A. Magnet 58A is characterized by two portions 66, 70. Portion 66 is a segment of a circle having a center point 74 on axis A1. Portion 70 is a segment of a circle having a center point at 78. The north pole N of the magnet 58A is disposed at one intersection of the portions 66, 70, and the south pole S of the magnet 58A is disposed at the other intersection of the portions 66, 70. In the embodiment depicted, portion 66 has the same radius as portion 70, and the concave sides of portions 66, 70 face one another. The magnet 58A circumscribes both center points 74, 78.

Sensor 62A is positioned on phalange 38A such that, as phalange 38A rotates with respect to phalange 38D about axis A1, the sensor 62A maintains a constant distance from portion 66 of the magnet 58A. The shape of the magnet 58A and the placement of the sensor 62A provide a linear relationship between angular position of the phalange 38A with respect to phalange 38D and the change in magnetic field that is read by sensor 62A. In the embodiment depicted, sensor assembly 56A generates an approximately linear signal over a 150-degree usable range of angular positions.

Magnet 58A is mounted with respect to phalange 38D and sensor 62A is mounted with respect to phalange 38A, and thus sensor assembly 56A measures the rotational position of phalange 38A with respect to phalange 38D. Magnet 58B is mounted with respect to phalange 38B and sensor 62B is mounted with respect to phalange 38A, and thus sensor assembly 56B measures the rotational position of phalange 38B with respect to phalange 38A. Magnet 58C is mounted with respect to phalange 38C and sensor 62C is mounted with respect to phalange 38B, and thus sensor assembly 56C measures the rotational position of phalange 38C with respect to phalange 38B. A sensor assembly (not shown) substantially identical to sensor assemblies 56A-56C measures the position of phalange 38D with respect to base member 37 as phalange 38D rotates about axis A4.

In the embodiment depicted, the range of motion of joint 42A (proximal pitch) is -10° to 95° ; the range of motion of joint 42B (medial pitch) is 0° to 120° ; the range of motion of joint 42C (distal pitch) is 0° to 70° ; and the range of motion of joint 42D (yaw) is -20° to 20° .

Referring to FIGS. 12 and 14, finger 19A is mounted to the base structure 34 by a shock mount 82. The shock mount 82 includes a keyed shaft 86, a retainer ring 90, and a spring 94. The cylindrical shaft 86 is slidingly engaged within a cylindrical cavity 98 defined by the base structure 34. The rectangular key 102 extends within a rectangular portion 106 of cavity 98 to prevent rotation of the shaft 86 with respect to the structure 34. The retainer ring 90 is larger than the cavity 98

and thus retains the shaft **86** inside the cavity **98**. The spring **94** biases the shaft **86** outward and absorbs shocks that may be exerted on the finger **19A**.

It should be noted that, although the tendons **46A-46D** are depicted in FIGS. **9** and **11** as being external to the phalanges **38A-38D**, each of the tendons is routed through a respective internal guide channel. In the embodiment depicted, tendons **46A-46D** are braided polymers. Referring to FIG. **15**, the finger **19A** includes inserts, such as the ones shown at **110A**, **110B**, **110C**, where sliding friction of the tendons **46A-46D** occurs. The inserts **110A**, **110B**, **110C** are softer and weaker than the structural material of the phalanges **38A-38D**, and are selectively replaceable. In one embodiment, the tendons **46A-46D** comprise Vectran® and the inserts **110A**, **110B**, **110C** are bronze.

Referring to FIGS. **16** and **17**, the finger **19A** is configured to accommodate, for each pair of opposing tendons, a respective bidirectional tendon terminator **114A**, **114B**. More specifically, tendon **46A** extends on the non-palmar, or dorsal, side of axes **A1** and **A2**, and is mounted to phalange **38B** via tendon terminator **114A**. Tendon **46B** extends on the palmar side of axes **A1** and **A2**, and is mounted to phalange **38B** via tendon terminator **114A**. Similarly, tendon **46C** extends on the non-palmar side of axis **A1** and is mounted to phalange **38A** by tendon terminator **114B**. Tendon **46D** extends on the palmar side of axis **A1** and is mounted to phalange **38A** by tendon terminator **114B**.

Referring to FIG. **18**, a phalange **38** is shown in a cutaway, perspective view. Phalange **38** is representative of phalanges **38A-38C**, and sensor **54** is representative of sensors **54A-54C**. Phalange **38** defines a chamber **118** that is characterized by an opening **122**. Compact electronics **126** are contained within the chamber **118**. The functions of the electronics **126** include providing power to the sensors, collecting analog sensor data, converting analog signals to digital signals, multiplexing digital signals, and communicating data to upstream electronics. Referring again to FIG. **16**, the finger **19A** includes a central channel **128** that extends the length of the finger **19A** to accommodate the wiring required to connect the sensors, the compact electronics, and the upstream electronics.

Referring to FIGS. **18** and **19**, sensor **54** includes a sensor cover **130** and a sensor assembly **134**. The sensor assembly **134** generates sensor signals in response to loads applied to the sensor cover **130**, and transmits the sensor signals to the electronics **126**. The sensor assembly **134** is generally C-shaped, and is characterized by a flange **138**, **142** at each end. Each flange **138**, **142** abuts a respective shoulder **146**, **150** formed by the phalange **38**. The flanges **138**, **142** of the sensor assembly **134** also partially define respective slots **154**, **158**.

A C-shaped clip **162** includes a flange **166**, **170** at each end. The clip **162** extends across opening **122** to enclose the chamber **118** and the electronics **126** contained therein. Each flange **166**, **170** engages a respective one of the slots **154**, **158** to secure the clip **162** to the sensor assembly **134**, and to retain the sensor assembly **134** to the phalange **38**. The cover **130** is mounted to the sensor assembly **134** by screws **174**.

Referring again to FIG. **16**, the finger **19A** is designed to accommodate a glove or skin-like covering (not shown) for protection from the environment and to provide grip surfaces to the tactile sensors that are appropriate for a specific task. The finger **19A** includes a plurality of threaded attachment holes **178** designed to secure the glove or skin-like covering to the finger, preventing slippage at the critical locations.

While the best modes for carrying out the invention have been described in detail, those familiar with the art to which

this invention relates will recognize various alternative designs and embodiments for practicing the invention within the scope of the appended claims

The invention claimed is:

1. A robotic hand assembly comprising:

- a base structure;
 - a finger having first, second, and third phalanges;
 - a first joint operatively connecting the first phalange to the base structure such that the first phalange is selectively rotatable with respect to the base structure about a first axis;
 - a second joint operatively connecting the second phalange to the first phalange such that the second phalange is selectively rotatable with respect to the first phalange about a second axis; and
 - a third joint operatively connecting the third phalange to the second phalange such that the third phalange is selectively rotatable with respect to the second phalange about a third axis;
 - a first tendon being operatively connected to the second phalange such that tension in the first tendon urges the second phalange to rotate about the second axis in a first direction;
 - a second tendon being operatively connected to the second phalange such that tension in the second tendon urges the second phalange to rotate about the second axis in a second direction;
 - a third tendon being operatively connected to the first phalange such that tension in the third tendon urges the first phalange to rotate about the first axis in the first direction;
 - a fourth tendon being operatively connected to the first phalange such that tension in the fourth tendon urges the first phalange to rotate about the first axis in the second direction;
- wherein the third joint is kinematically linked to the second joint such that the position of the third phalange with respect to the second phalange is determined by the position of the second phalange with respect to the first phalange.

2. The robotic hand assembly of claim 1, further comprising a linkage that is rotatably mounted with respect to the first phalange and rotatably mounted with respect to the third phalange to kinematically link the third joint and the second joint.

3. The robotic hand assembly of claim 2, wherein the linkage includes a spring.

4. The robotic hand assembly of claim 1, further comprising a fourth phalange rotatably connected to the first phalange by the first joint; and

- a fourth joint operatively connecting the fourth phalange to the base structure such that the fourth phalange is selectively rotatable with respect to the base structure about a fourth axis.

5. The robotic hand assembly of claim 4, wherein the fourth axis is substantially perpendicular to the first, second, and third axes.

6. The robotic hand assembly of claim 5, wherein the first and second tendons are routed on a first side of the fourth axis; and

- wherein the third and fourth tendons are routed on a second side of the fourth axis.

7. The robotic hand assembly of claim 1, further comprising at least one insert;

- wherein at least one of the first, second, third, and fourth tendons contacts the insert; and
- wherein the insert is softer or weaker than the phalanges.

8. The robotic hand assembly of claim 1, further comprising a shock mount that operatively connects the finger to the base structure.

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