



UNSW
SYDNEY



Tactile Sensing for Dexterous Robotic Manipulation

Robots need a sense of touch if they are to match human capabilities. This patented technology replicates the human sense of touch without being limited by size, strength, environment or fatigue.

Competitive advantage

- Soft sensor design can measure 3-D localised force, 3-D localised deflection, 3-D localised vibration, torque, incipient slip and friction at the gripper-object interface. All are the essential parameters for determining whether an object is securely grasped
- The size, density, compliance, measurement range and sensitivity of the sensor can be customised and there are no electronics in the contact surface
- The sensor is resistant to shock, water and chemicals and can be food safe

Impact

- Enhanced remote tactile sensing for applications such as surgery, unmanned exploration and disarming mines
- Improved robotic gripping for applications such as pick-and-place, disaster response and assistance robots
- More-precise slip sensing in feet for legged robots and exoskeletons

Successful applications

- Demonstrated large scale sensor prototype with 99% accuracy and 98% precision in force and deflection measurement.
- Demonstrated large scale intelligent gripper prototype with ability to grasp objects of varying friction and weight using an optimal grip force
- Participation in the Commonwealth Scientific and Industrial Research Organisation (CSIRO) ON Accelerate start-up accelerator program for commercialisation

Our partners

- US Office of Naval Research Global

More Information

Dr Heba Khamis

Graduate School of Biomedical Engineering

T: +61 (0) 450 505 582

E: h.khamis@unsw.edu.au

UNSW Knowledge Exchange

knowledge.exchange@unsw.edu.au

www.capabilities.unsw.edu.au

+61 (2) 9385 5008