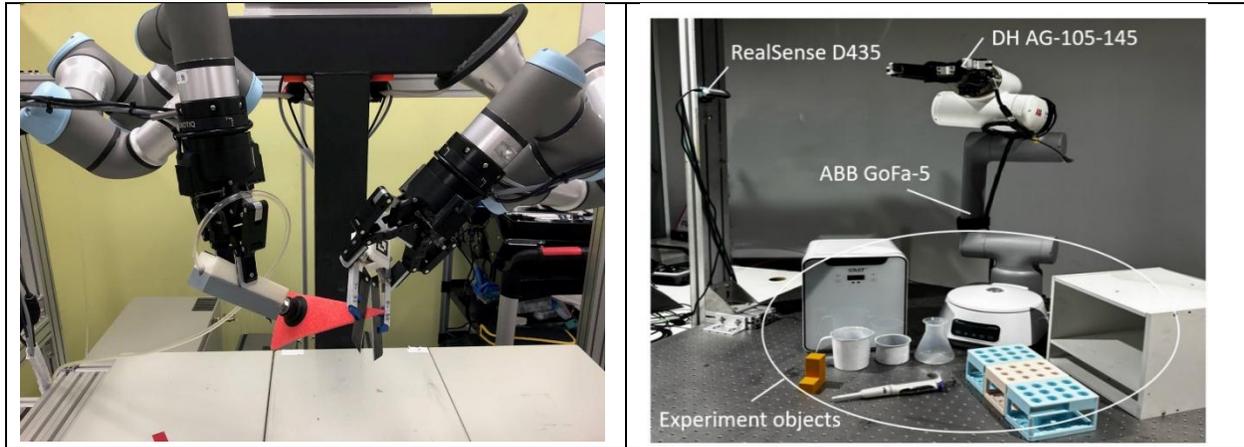


Project Summary

Project title “Dual Arm Robotic Grasp Planning and Manipulation Considering Soft Contact”



Objectives

This project proposes a robotic grasping and manipulation planning method that considers grasping with compliant contact. The method utilizes flexible deformation of the gripper and **the object to:**

- Enhance adaptability to complex geometries.
- Improve grasping redundancy and robustness.
- Enable the development of soft grippers with diverse grasping mechanisms.
- Support continuous dual-arm cooperative manipulation in constrained spaces.

Partners

Prof. Hu Zhengtao from Shanghai University, School of Mechatronic Engineering and Automation.

Funding Agency

Science and Technology Commission of Shanghai Municipality (STCSM).

Expected Results

Academic Outputs:

- Publish 4 high-level papers.



The
BRITISH UNIVERSITY
IN EGYPT

- Participate in 2 top conferences in robotics.

Talent Development:

- Supervise postgraduate and undergraduate students working on related research topics.