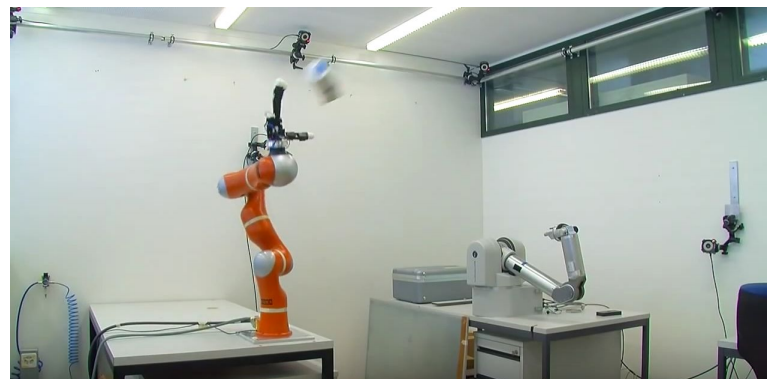


Kōan 1: Soft catch

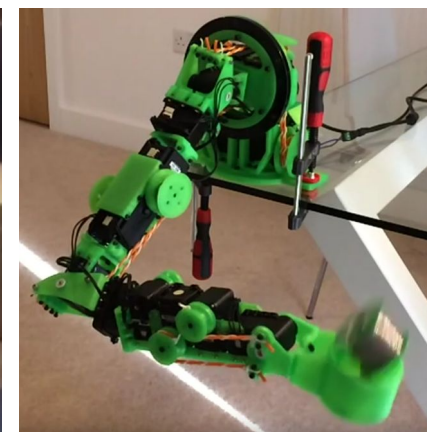
- Reliably catching objects is hard, but progress is being made (see videos)
- Can a 'soft' embodiment simplify the problem? If so, how?
- One source of inspiration could be the human body - what is the key to a successful catch?
- How does a passively compliant structure increase the time available to close the hand? How/why is the control simplified? Is it?
- Can a 'soft' embodiment also simplify the needed sensing?
- See for example the GummiArm*



Robot catches a variety of objects (w/ globally tracked markers): <https://youtu.be/M413ILWvrbl>



Soft octopus arm: <https://youtu.be/vSRgO6GShTo>



Passive "catch": <https://youtu.be/sBEPA2ymCbk>

*Do you have other ideas?
Feel free to be creative!*

* <https://github.com/mstoelen/GummiArm>