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Robust detection of absence of slip in robot hands and feet

Yerkebulan Massalim, Zhanat Kappassov Member, IEEE, Huseyn Atakan Varol Senior Member, IEEE and Vincent Hayward Fellow, IEEE

Abstract—We describe an algorithm that can robustly decide whether a grip or a footstep is secure given data collected from at least two independent sensors. This algorithm is based on the observation that if there is an absence of slip, then, owing to the high velocity of mechanical waves in solids, the two sensor signals must be highly correlated, even in the presence of internal or external perturbations. The statistical distance between signals collected during slip and non-slip phases, regarded as random distributions, also provides a continuous measure of graspability or walkability of an object being held or a ground being stepped on. We tested the algorithm on a bench using micro-electro-mechanical system (MEMS) accelerometers and with a variety of materials of different surface roughnesses. We also discuss the applications of this non-slip/slip discrimination algorithm and its putative relationship with human gripping behavior.

Index Terms—Slip detection, tactile sensing, haptic manipulation, dexterous manipulation.

I. INTRODUCTION

Manipulation and locomotion crucially depend on friction. When the tangential load sustained by two surfaces in contact exceeds a threshold, slip takes place. Owing to numerous factors, the frictional properties of contacts are difficult to predict. However, successful manipulation and locomotion depend on the absence of slip between the appendages of a robot and external objects. In robotics, sensing techniques able to detect slip have long been recognized to be essential for dexterous manipulation and secure locomotion.

One approach to slip detection is an attempt to imitate the features of the glabrous skin of primates. As early as the 1970s, there were efforts to create sensitive artificial skins for grip adjustment [1]. These approaches are discussed in numerous surveys [2]–[5]. Nevertheless, the neural processes that subserve slip detection during grip adjustment are still not fully explained [6], [7]. Another approach is to take advantage of mechanical load sensors that can be integrated into robot extremities, leading to another family of approaches termed intrinsic sensing [8]. Intrinsic sensing can also be applied to slip detection [9].

Sensors or systems of sensors do not detect slip per se. Sensors report some aspects of the consequences of slip in order to trigger appropriate corrective actions. Examples of such actions include tightening a grip, reconfiguring fingers, reducing stride impetus, or adapting posture. Slip detection is accomplished by algorithms that use sensor data to decide that slip has occurred, or is about to occur, between an extremity and an external object. Numerous algorithms surveyed in the next section are tailored to the type of sensor used to collect mechanical signals.

The present article describes an algorithm that depends only weakly on the type of sensor used to collect mechanical signals. An essential requirement for its operation, however, is that there must be at least two sensors signals reporting mechanical events arising from contacts with a single common object. The algorithm could be extended to multiple sensors but two are sufficient.

Slip between surfaces is always associated with a noisy component corresponding to velocity fluctuations caused by brief occurrences of negative damping in frictional phenomena. Sliding surfaces, hard or soft, rough or smooth, even lubricated, all produce frictional noise. The magnitude and the properties of frictional noise depend on a number of factors. These include the materials in contact, the net sliding velocity, the topography of the surfaces, the internal structure of the object, the load, abrasion, interstitial contaminants, and the history of the contact [10]–[12].

Frictional fluctuations can have periodicity, as in squeals or bow-string interactions, but are often predominantly stochastic. Fluctuations are observed even when friction is extremely
low [13]. Slip detection should be robust to many possible perturbations, for example, vibrations arising from the robot’s actuators and transmissions or from the interactions of a gripped object with external objects.

Slip detection ought to be free from as many assumptions as possible, i.e., independent of the assumed models of friction. To progress toward this goal, we propose that an absence of slip can be reliably determined during a grip or a footstep, by investigating the similarity between signals from sensors responding to contact with a common solid object. In the absence of slip, the signals exhibit a high degree of similarity since the wavelength of mechanical waves in solids is generally much greater than the distance between two sensors. At one thousand Hertz, the wavelength of mechanical waves in wood is about five meters; in granular materials, such as soils, it is of the order of fifty centimeters [14], [15].

II. RELATED WORKS

In order to achieve robotic manipulation, the detection of slip was viewed as an imperative necessity early on. Hirochika Inoue [16] concluded, “Force feedback enables the robot to guide a peg into a hole quite reliably given that the parts do not slip in the hand. From a practical point of view, it is also important to develop a general-purpose hand that prevents ‘slip’ or that at least detects its occurrence”.

Baits et al. [17] had already demonstrated automatic grip adjustment by detecting vibrations using piezoelectric sensors in contact with a gripped object. At the same time, Ring and Welburn [18] observed the Cattaneo-Mindlin contact mechanics in human fingers acting against a rigid counter surface. The Cattaneo-Mindlin contact mechanics describes partially sliding contacts as a mixture of stick and sliding regions. They noted the time course for the transition to fully-developed slip to last about 300 ms (value later confirmed in [19]) and developed a sensor designed to directly resolve the state of a contact.

Research in hand prostheses anticipated the need to detect slip, ushering families of methods concerned with the analysis of the temporal properties of sensor signals available in a gripping device (Section II-A); the analysis of the spatiotemporal evolution of a population of sensors (Section II-B); and the resolution of contact states from force measurements (Section II-C). Efforts have been made to develop sensing techniques to measure slip directly (Section II-D). Although the literature on slip detection is often intertwined with the description of tactile sensors, the above classification can guide the discussion of slip detection algorithms.

A. Temporal Properties of Tactile Signals

Dornfeld and Handy [20] pointed out the possibility of taking advantage of the acoustic emissions of sliding contacts to detect slip. Howe and Cutkosky [21] proposed to threshold the amplitude of the signal given by a miniature accelerometer integrated in a flexible envelope wrapped around a robot finger. Tremblay and Cutkosky [22] observed that the slip signal was more reliably detected from accelerometers located away from the region of contact. Kyberd and Chappell [23] described an algorithm that computed a discrete approximation of the temporal gradient of signals arising from force-sensing resistors in the palm and fingertips of a multi-fingered prosthetic hand. This algorithm gave an approximation of the direction of object slip. Later, Kyberd et al. [24] discussed the automatic tightening of a grip from cumulative counts of slip events detected by microphones in the fingers of a prosthetic hand. Goger et al. [25] employed the short-term Fourier transform to process a signal given by a piezoelectric polyvinylidene difluoride (PVDF) polymer sensor. The frequency-domain representation was further processed through feature detection and nearest-neighbor classification to decide whether a slip occurred. Takenawa [26] embedded miniature magnets in artificial skin. By Lenz’s law, the oscillation of these magnets induced voltages in neighboring coils. The occurrence of slip was decided through the detection of spikes caused by the release of stored elastic energy. In another work, researchers placed accelerometers in the grippers of a robot [27]. During grip, the slip was detected from the magnitude of the signal during specific phases of the manipulation. Taking advantage of a piezoresistive film sensor, Teshigawara et al. [28] used the Haar discrete wavelet transform (DWT) to detect specific signal fluctuations that were indicative of slip. Heyneman and Cutkosky [29] observed that under the assumption of linearity the mapping from input vibrations to the sensor outputs is the sum of the signal resulting from the coupling object-finger and the vibrations of the held object. The analysis of coherence among sensor signals in the frequency domain enabled the offline classification of slip types from data recorded by a robot gripper with two BioTac sensors (Syntouch, Montrose, CA). Using a single BioTac sensor, Su et al. [30] used an artificial neural network comprising a fifty-neuron hidden layer to classify slips into sliding and pivoting contacts. Veiga et al. [31], also with BioTac sensors, programmed a support vector machine to predict slip using features extracted from raw sensor data.

B. Spatio-Temporal Evolution of a Population of Sensors

Stojiljković and Clot [1] covered a prosthetic hand with a soft artificial skin made of an electrically conductive elastomer. The inner layer of this skin featured a dense array of electrodes. Contact with objects reduced the resistance of each cell. Each sensing cell produced one slowly-adapting output and one fast-adapting output. An artificial neural network implemented a lateral inhibition algorithm that provided separate fast-adapting excitatory and slowly-adapting inhibitory signals. These signals were combined to detect spatial and temporal mechanical gradients whose magnitude determined the activation of the motors. This way, the slip was prevented for both soft and hard gripped objects. From prior work suggesting the use of stochastic filtering to process data available from a population of sensors [32], Ho and Hirai [33] used image processing to estimate the ratio of the stuck contact area to the gross contact area to adjust grip during bi-digital object lifting. Yuan et al. [34] collected dense data using a GelSight sensor [35] and used image processing to estimate the state of the Cattaneo-Mindlin contact mechanics. Meier et al. [36] used data acquired from arrays of piezoresistive sensors pressed
against a rigid object and, from features extracted in the frequency domain, trained a convolutional neural network to distinguish between sliding and pivoting contacts. Roberge et al. [37] used unstructured data acquired from capacitive sensing arrays and converted them to the frequency domain to give a sparse representation of these data. After training, a support vector machine algorithm was able to reliably identify slips within the dataset. James et al. [38] used an optical tactile sensor, the TacTip, to collect image-like data during a variety of interactions with surfaces. A support vector machine could accurately detect slip from the temporal evolution of the image data. Eghtedari et al. [47] took advantage of counter surface, however, was required to possess special magnetic properties. Steindler [46] employed contactless inductive transducers. The trains of electrical pulses by closing a circuit. D’Alessio and suggested that because slip is by definition the relative dis-

C. Contact State Resolution from Force Measurements

Ring and Welburn [18] described a sensor that measures the magnitude of the interaction force between a finger and an object. Thus, assuming a known coefficient of friction, the slip was prevented by driving a single-motor of the two-fingered prosthetic hand proportionally to this signal. The algorithm was similar in its principle to what is realized by an industrial scissor grab lifting clamp with the difference that the gripping action was independent of the direction of external disturbances. Building on the work of Bicchi et al. [8] on intrinsic sensing, Melchiorri [40] described a geometrical method to determine the occurrence of slip from the location of the center of rotation of a body in contact with a rigid surface using a combination of force and distributed pressure sensing. Wettels et al. [41] used BioTac sensors mounted on an Otto Bock Michelangelo anthropomorphic robotic hand to resolve the contact force through a Kalman filter. Song et al. [42] mounted six-axis force/torque sensors on the fingertips of a three-fingered BarrettHand robotic hand and used an extended Kalman filter to estimate the ‘breakaway’ force ratio from the coefficients of a solid friction model, namely the LuGre model [43]. Yussof et al. [44] designed a robotic fingertip with forty-one ‘feelers’ whose deflections and compressions were optically measured. The data were used to detect the direction of slip to maintain a stable grip.

D. Direct Measurement of Slips

Some “computation-free” techniques for slip detection are mentioned in this subsection. Tomović and Stojićković [45] suggested that because slip is by definition the relative displacement of two surfaces in contact, sensors could be devised to detect slip directly. Notably, one of their designs involved a needle-like pointer set inside an artificial skin layer such that slip entrained its lateral movements, generating trains of electrical pulses by closing a circuit. D’Alessio and Steindandler [46] employed contactless inductive transducers. The counter surface, however, was required to possess special magnetic properties. Eghtedari et al. [47] took advantage of the properties of a photoelastic layer interposed between a polarizer and an analyzer to produce slip-sensitive fringe patterns that could be imaged. Later, [48] used this principle to produce a continuous signal during slip. Gofuku et al. [49] installed one illuminator and two adjacent reflected light detectors in a robot gripper. Researchers estimated the slip velocity using signal shift estimation by cross-correlating the two signals in the frequency domain. Accoto et al. [50] described a micro-sensor that exploited the dependency of heat diffusion upon the relative velocity of two surfaces in contact to detect slip. Kondratenko et al. [51] revisited the technique of the oscillating pin interacting with a held object and sensed the slip-induced oscillations by capacitive detectors.

III. Algorithm for Absence of Slip Detection

The slip conditions for a gripping or a stepping system as in Fig. 1 may be represented by

\[
\text{no slip: } \begin{align*}
    s_1(t) &= p_1(t), \\
    s_2(t) &= p_2(t),
\end{align*}
\]

\[
\text{slip: } \begin{align*}
    s_1(t) &= s_1(t) + p_1(t), \\
    s_2(t) &= s_2(t) + p_2(t).
\end{align*}
\]

where \(s_1(t)\) and \(s_2(t)\) stand for the signals acquired by the sensors, \(s_1(t)\) and \(s_2(t)\) the signals arising from frictional noise, and \(p_1(t)\) and \(p_2(t)\) are the signals resulting from unknown external and internal perturbations. As discussed earlier, \(p_1(t)\) and \(p_2(t)\) are expected to be similar since they arise from common sources while \(s_1(t)\) and \(s_2(t)\) are expected to be different since they arise from sliding noise.

Cross-correlation is a measure of the similarity between signals. The cross-correlation of two continuous-time signals is computed from their reversed convolution. Since in practice signals are available in discrete time, cross-correlation can be computed over a finite-length window from the inner product of two vectors. In signal analysis, an approach commonly adopted to arrive at a practical algorithm is to consider the signals to be zero-mean random time-series of size \(n\). We make this assumption for the sensor signals \(s_1(t)\) and \(s_2(t)\).

The computation of the zero-delay normalized cross-correlation, \(\text{NCC}(s_1, s_2)\), between the two vectors, \(s_1 = [s_1(0), \ldots, s_1(n-1)]^T\) and \(s_2 = [s_2(0), \ldots, s_2(n-1)]^T\) can...
then be written as

\[ \text{NCC}(s_1, s_2) = \frac{\sum_{i=0}^{n-1} s_1(i)s_2(i)}{\sqrt{\sum_{i=0}^{n-1} s_1^2(i) \sum_{i=0}^{n-1} s_2^2(i)}} \]

\[ = \frac{s_1 \cdot s_2}{n \sqrt{\sigma(s_1)\sigma(s_2)}} \]

(3)

(4)

where \( \sigma(s_1) \) and \( \sigma(s_2) \) represent the variances of \( s_1 \) and \( s_2 \), respectively and \( s_1 \cdot s_2 \) denotes the dot product of the vectors \( s_1 \) and \( s_2 \).

NCC for the non-slip case can be written using (1) and (4) as

\[ \text{NCC}(s_1, s_2) = \text{NCC}(p_1, p_2) = \frac{p_1 \cdot p_2}{n \sqrt{\sigma(p_1)\sigma(p_2)}}. \]

(5)

Since \( p_1 \) and \( p_2 \) are highly correlated, we can write

\[ \text{NCC}(p_1, p_2) = \frac{p_1 \cdot p_2}{n \sqrt{\sigma(p_1)\sigma(p_2)}} \approx 1. \]

(6)

In other words, NCC for the non-slip case must be close to one. Similarly, in the case of slip, using (2) and (4), NCC can be written,

\[ \text{NCC}(s_1, s_2) = \frac{(p_1 + s_1) \cdot (p_2 + s_2)}{n \sqrt{\sigma(p_1 + s_1)\sigma(p_2 + s_2)}} \]

\[ = \frac{p_1 \cdot p_2 + s_1 \cdot p_2 + s_2 \cdot p_1 + s_1 \cdot s_2}{n \sqrt{\sigma(p_1)\sigma(p_2)}}. \]

(7)

Noting that frictional noise signals are uncorrelated with the perturbation signals and with each other, we can assume that,

\[ s_1 \cdot p_j = 0 \quad \forall i, j \in \{1, 2\}, \]

(8)

\[ s_1 \cdot s_2 = 0. \]

(9)

Substituting (8) and (9) into (7) gives

\[ \text{NCC}(s_1, s_2) = \frac{p_1 \cdot p_2}{n \sqrt{(\sigma(s_1) + \sigma(p_1))(\sigma(s_2) + \sigma(p_2))}}, \]

(10)

and by posing \( k_1 = \sigma(s_1)/\sigma(p_1) \) and \( k_2 = \sigma(s_2)/\sigma(p_2) \), (10) becomes

\[ \text{NCC}(s_1, s_2) = \frac{p_1 \cdot p_2}{n \sqrt{\sigma(p_1)\sigma(p_2)}} \frac{1}{\sqrt{(1+k_1)(1+k_2)}}. \]

(11)

Noting the high correlation of \( p_1 \) and \( p_2 \), as in (6), we can simplify this expression to

\[ \text{NCC}(s_1, s_2) \approx \frac{1}{\sqrt{(1+k_1)(1+k_2)}}. \]

(12)

We conclude that, counterintuitively, with this algorithm the greater the perturbations are, the more reliable is the detection of an absence of slip. For example, a robot gripping a part may purposefully cause collisions with external objects to reduce the uncertainty of a secure grip. Likewise, a robot may apply an anticipatory, exaggerated load on a foot to ascertain that it would not slip.

An absence of slip can be detected when the NCC measure is close to one and additional information may be obtained from the analysis of the signals. Of particular interest is the possibility of gauging the “graspsability” of an object or the “walkability” of a terrain. To this end, a robot may quantify how frictional noise differs from background perturbation. For example, a smooth slippery surface would be such that the sensor signals are similar whether or not there is slip.

In keeping with a statistical approach, such evaluation may be accomplished through a distance measure between distributions represented by a vector normalized to a vector of the NCC values during slip, \( \bar{s} \), and to another vector of NCC values, \( \bar{p} \), when there is no slip. A direct measure can be then provided by the Hellinger distance between discrete distributions known for its efficiency and robustness [52]. This distance, \( H(\bar{s}, \bar{p}) \) can be computed as follows,

\[ H^2(\bar{s}, \bar{p}) = \frac{1}{2} \sum_{i=0}^{n-1} \left( \sqrt{s(i)} - \sqrt{p(i)} \right)^2, \]

(13)

\[ = \frac{1}{2} \left\| \sqrt{\bar{s}} - \sqrt{\bar{p}} \right\|_2^2, \]

(14)

\[ = 1 - \sum_{i=0}^{n-1} \sqrt{s(i)p(i)}. \]

(15)

The Hellinger Distance provides us with a similarity measure of two probability distribution functions. When its absolute value approaches to one, the distribution are totally different. When its value is close to zero, the distributions are similar. This expression allows one to estimate objectively how well the NCC value can discriminate slip from non-slip in given conditions, giving robustness.

The algorithm could be instantiated with many other similarity measures other than NCC, although this latter measure has the advantage of being particularly economical to compute. For instance, adopting a deterministic approach, the Fréchet distance between \( s_1 \) and \( s_2 \) could be employed to evaluate their similarity. This method could also have a statistical interpretation [53]. Another statistical method could appeal to the Kolmogorov-Smirnov empirical test to compute the probability that the samples in vectors \( s_1 \) and \( s_2 \) or in \( u \) and \( v \) were drawn from a common, yet unknown, distribution. Any of these methods is expected to produce qualitatively similar results. The choice of measures, being entirely application-dependent, is not discussed further.

IV. EXPERIMENTS

A. Experimental Setup

An experimental setup (see Fig. 2A) was constructed to systematically test the detection algorithm over a wide range of sliding velocities, materials, and interaction forces. This testbed comprised a slider-crank mechanism that moved interchangeable samples against a pair of sensorized robot gripper pads (Model ENG 100, SCHUNK GmbH, Germany) under the action of a speed-reduced DC motor (Model EC 380619, Maxon Group, Switzerland). The samples were guided by four rollers. A slider-crank mechanism with two adjustable hard-stops entrained the movements of the sample while providing periods of rest. The sample came to a stop each time the mechanism came close to a singular configuration. A linear encoder (AEDR-8300, Broadcom, CA, USA) with a resolution of 0.12 mm provided the “ground truth” for the speed of the
sample by differentiating the encoder signal numerically and smoothing it through a 500-sample moving average.

The gripper pads could be configured to either grip the sample or press against it from the same side, see Figs. 2B and 2C. These components were held in place by a quick-connect aluminum frame defining a coordinate system with the z-axis along the direction of the movements of the sample and the z-axis in the plane of the frame, see Fig. 2A.

The sensors were 3-axis MEMS accelerometers (ADXL 335, Analog Devices, MA, USA) rigidly connected to the gripper pads and set against elastomer supports to prevent rattling as shown in Fig. 2D. The z-axes of the accelerometers were aligned with the z-axis of the frame. The pads could be oriented around the common z-axis by an angle α between the x-axes of the accelerometers and the frame. Data were acquired by a custom-made analog-to-digital converter board sampling the analog signals at a rate of 8.0 kHz.

### B. Testing Conditions

Testing was performed at three motor speeds (average speeds of the samples: 0.8, 0.16, and 0.24 m/s) and with three materials (aluminum, plastic, and wood). The grasping or pressing forces were set at two levels for each material (Table I). The gripping configuration was tested at four different angles α of orientation (0°, 15°, 30°, and 45°). In the pressing configuration, α was zero. These parameters resulted in seventy-two (3 × 2 × 4) conditions in the gripping configuration and eighteen (3 × 3 × 2) conditions in the pressing configuration. Additional external perturbations were caused by placing a vacuum pump producing 110 Hz vibrations in the vicinity of the testbed. Separate tests were performed with glass samples (see the last row of the Table I).

The wooden sample is clearly a favorable case for the discrimination of non-slip and slip contact states. Figure 4 shows the evolution of H, computed for the sensor signals obtained between these two states when the optimal conditions were altered.

Figure 4A shows the evolution of H for different gripper orientations. It shows that the discrimination robustness, not the performance, was sensitive to the orientation and that the robustness was optimal when the acceleration was measured in the direction of slip, which makes sense intuitively. Figure 4B

<table>
<thead>
<tr>
<th>material</th>
<th>roughness [nm]</th>
<th>lower force [N]</th>
<th>higher force [N]</th>
</tr>
</thead>
<tbody>
<tr>
<td>aluminum</td>
<td>121</td>
<td>15</td>
<td>25</td>
</tr>
<tr>
<td>plastic</td>
<td>372</td>
<td>20</td>
<td>35</td>
</tr>
<tr>
<td>wood</td>
<td>6381</td>
<td>6</td>
<td>12</td>
</tr>
<tr>
<td>glass</td>
<td>45</td>
<td>40</td>
<td>51</td>
</tr>
</tbody>
</table>
shows that the discrimination robustness of the system is
greater for the gripping configuration than for the foot con-
figuration. This result could be explained by the fact that the
signal might have leaked between the two sensors in greater
proportion for the foot configuration than for the gripper con-
figuration, decreasing the distance between the signal acquired
during the different contact states. Figure 4C reports what
could be intuitively predicted, namely, that smoother surfaces
decrease robustness. Finally, Fig. 4D shows that robustness
is unaffected by the level of gripping force, which is also
intuitively correct, since pressure is unlikely to modify the
correlation of the frictional noise signals.

![Fig. 4: Hellinger distance in different testing conditions. (A) Gripper orientation with respect to slip velocity. (B) One-sided foot configuration. (C) Material and roughness. (D) Grip force.](image)

**VI. DISCUSSION AND CONCLUSION**

The newly introduced non-slip detection algorithm by cross-
correlation can compute a non-slip/slip decision within a few
microseconds using an ordinary microcontroller. The decision
delay is commensurate with the length of the buffer used
to store past data. In the case of the present experiments,
the length of this buffer was 500 samples, corresponding to
delay is commensurate with the length of the buffer used
during the different contact states. Figure 4C reports what
could be intuitively predicted, namely, that smoother surfaces
decrease robustness. Finally, Fig. 4D shows that robustness
is unaffected by the level of gripping force, which is also
intuitively correct, since pressure is unlikely to modify the
correlation of the frictional noise signals.

It should be recognized, however, that in these cases the very
notion of absence of slip is elusive.

Besides its computational efficiency and absence of tuning,
a prominent practical advantage of the algorithm is the low
cost incurred for its implementation. Here, the sensors were
consumer-grade, widely available mass-produced accelerom-
eters. Many other types of sensors could be used for the
purpose of responding to the vibrations of the pads in contact
with objects or the ground. For example, low-cost monomorph
disc piezoelectric units respond with high sensitivity to minute
vibrations. Miniature microphones would also be applicable.

Another key advantage of this algorithm is its ability to
be implemented as a retrofit on most existing robots, whether
they have grippers, hands, feet, or even wheels. In the case
of wheels, the implementation might not be straightforward
because the sensors would have to be configured so that both
always in close vicinity of the contact with the ground. The
signals would also have to be routed through the hubs. The
algorithm could also be easily retrofitted in most motorized
prosthetic hands and grippers with minimal effort. Lastly, not
the least of these applications could be to human hands and
feet since vibratory signals propagate the tissues of human
extremities [55], [56]. Sensorized gloves and shoes could also
be an interesting option.

It is tempting to draw parallels with human gripping. To
date, research has focused on discovering tactile cues that can
be used to detect slip. Westling and Johansson demonstrated
that participants with anesthetized fingers would adjust their
clip to the weight of objects but not to their frictional
properties, thus demonstrating the existence of a physiolog-
ic mechanism that responds to slip [57]. The authors later
demonstrated that fast-adapting mechanoreceptors found in
the glabrous skin of fingers responded before fully-developed slip
takes place between fingers and counter-surfaces in suddenly
loaded grips [6], [58]. A follow-up study confirmed through
electromyography (EMG) that motor adjustment takes place
about 130 ms after the start of an unexpected perturbation and,
importantly, is time-locked with the onset of friction-induced
vibrations [59]. The possibility exists that human gripping
activity may depend on estimating the correlation—or the
lack thereof—of sensor signals between or within fingers [7]
on the grounds that estimating correlation is a fundamental
computational process of neural systems [60].

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Huseyin Atakan Varol (M’09-SM’16) received the B.S. degree in mechatronics engineering from Sabanci University, Istanbul, Turkey, in 2005, and the M.S. and Ph.D. degrees both in electrical engineering from Vanderbilt University, Nashville, TN, USA, in 2007 and 2009, respectively. From August 2009 to August 2011, he was first a postdoctoral research associate and then a research assistant professor with the Center for Intelligent Mechatronics, Department of Mechanical Engineering, Vanderbilt University, Nashville, TN, USA. In 2011, he joined the faculty of Nazarbayev University, Nur-Sultan, Kazakhstan, where he currently chairs the Department of Robotics and directs the Institute of Smart Systems and Artificial Intelligence (ISSAI). His research interests include soft robotics, machine learning, variable impedance actuation, tensegrity, and embedded systems. He has published over 70 technical papers on related topics in international journals and conferences. Dr. Varol was a finalist for the KUKA Innovation Award in 2014. He was also the recipient of the IEEE International Conference on Rehabilitation Robotics Best Paper Award in 2009 and IEEE Engineering in Medicine and Biology Society Outstanding Paper Award in 2013.

Vincent Hayward (M’84-SM’04-F’08) was a postdoctoral fellow, then a visiting assistant professor at Purdue University in 1982, and joined CNRS, France, as Chargé de Recherches in 1983. In 1989, he joined the Department of Electrical and Computer Engineering at McGill University as an assistant professor and became a full professor in 2006. He is now a professor at Sorbonne Université, Paris, France (formerly Université Pierre et Marie Curie). He has published in journals, conferences, collective books, and co-founded spin-off companies, received best paper and research awards. He was on the editorial boards of the IEEE Transactions on Robotics, the ACM Transaction on Applied Perception, and the IEEE Transactions on Haptics. He was elected a member of the French Academy of Sciences in 2020.

Yerkebulan Massalim is a research engineer in Actronika SAS, Paris, France. He received the B.Eng. in electrical engineering in 2017 and M.S. in robotics in 2020 from Nazarbayev University, Nur-Sultan, Kazakhstan. From 2017 to 2020, he worked as a hardware engineer on several embedded systems projects. His research interests are haptics, tactile sensing, embedded systems, and machine learning.

Zhanat Kappassov (M’16), received the Specialist degree in radioengineering from the Tomsk State of Control Systems and Radioelectronics (TUSUR), Tomsk, Russia. Afterward, he worked in the Industrial Technology Research Institute (ITRI), Taiwan. He received his Ph.D. in robotics from the Institute of Intelligent Systems and Robotics (ISIR), Sorbonne Université (formerly Université Pierre et Marie Curie), Paris, France, in 2017. He is currently an assistant professor of robotics at Nazarbayev University, Nur-Sultan, Kazakhstan. His current research interests focus on tactile sensing for robot physical interaction and dexterous manipulation. He serves regularly as a reviewer for the IEEE Transactions on Robotics and IEEE conferences. His PhD thesis was nominated as the Best PhD Thesis 2017 by the GDR Robotique association in France.