Multi-finger Adaptive Robotic Gripper (Quantity – 2)

Number of fingers	3, with minimum two joints (digits)per finger
Finger joint type and mechanism	joints and Underactuated (adaptable)
Actuation	Only Electric
Joint sensor	Encoders (for each joint)
Maximum gripping force	At least 20 N
Grasping object diameter	Minimum: 5 mm or less , Maximum: 45 mm or more
Total weight	Maximum1.3 kg
Hardware interface compatibility	Should be modular and independently driven even in the absence of manipulator. With force, position and speed control for each finger and minimum 4 different grip modes
Programming Language	C++ and/or Python
Software Compatibility	1. Default API/GUI 2. Should have a ROS compatibility
Warranty	3 Years
AMC	Not necessary