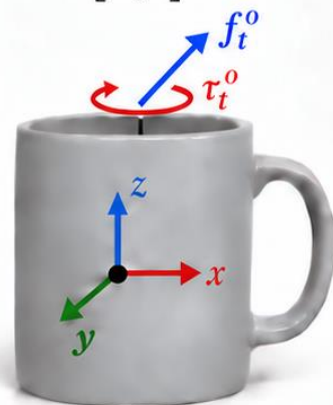




Object wrench (6D)

$$w_t^o = \begin{bmatrix} f_t^o \\ \tau_t^o \end{bmatrix} \in \mathbb{R}^6$$



Zoom: ring finger contact (side view)

