

---

## Errata: Computational Modelling at Hand-Eye Coordination

The Royal Society

*Phil. Trans. R. Soc. Lond. B* 1992 **338**, 417

doi: 10.1098/rstb.1992.0159

---

### Email alerting service

Receive free email alerts when new articles cite this article - sign up in the box at the top right-hand corner of the article or click [here](#)

## ERRATA

*Phil. Trans. R. Soc. Lond. B* **334**, 391–403 (1991)

All the observed universe has contributed to life

By R. E. DAVIES AND R. H. KOCH

The authors regret that an error in this paper requires the following corrections.

Page 391, column 2, lines 3–4 should read: ‘can only have come from a minimum average cosmic extrastellar volume of about  $2 \times 10^6$  that of Sun.’

Page 401, column 1, lines 11–12 should read: ‘560 g of P, we have calculated that about  $2 \times 10^5$  present solar volumes of average cosmic matter are . . .’.

Page 401, column 1, lines 22–23 should read ‘cosmic extrastellar volume really necessary to form a human becomes about  $2 \times 10^6$  equivalent solar volumes.’

Page 401, column 1, lines 29–30 should read ‘one order of magnitude precision, approximately  $10^7$  solar volumes of the cosmic extrastellar volume are required for K. However, . . .’.

Page 401, column 1, lines 38–39 should read ‘the results in table 2 for K as well as for P, the cosmic extrastellar volume needed to form a human is about  $2 \times 10^6$  solar . . .’.

*Phil. Trans. R. Soc. Lond. B* **337**, 351–360 (1992)

Computational modelling at hand–eye coordination

By ANDREW BLAKE

Page 353, figure 4 should appear as:

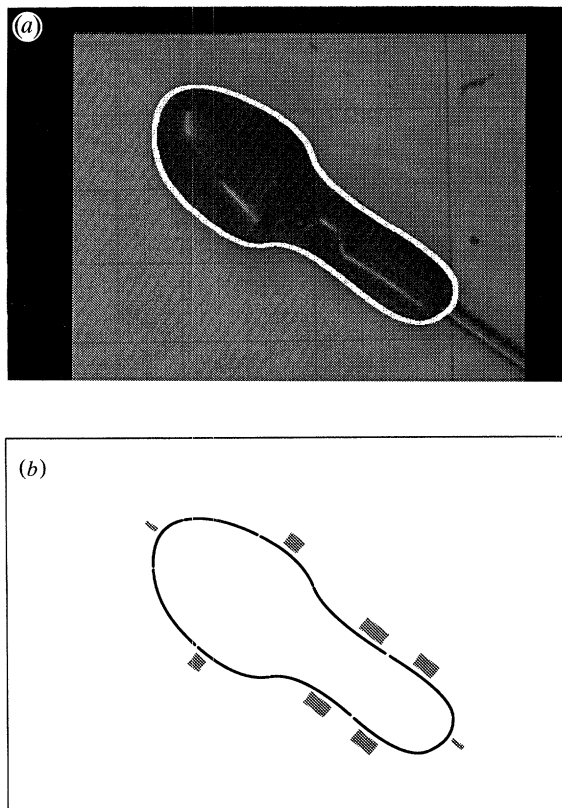


Figure 4. (a) A screwdriver, as seen by the robot’s camera, with a ‘dynamic contour’ locked onto the outline of its handle. (b) There are four seed grasps of type I (see figure 3), the most stable of which are the natural grasps across the handle. The other, much less stable but still feasible, is longitudinal.

*Phil. Trans. R. Soc. Lond. B* (1992), **338**, 417  
Printed in Great Britain

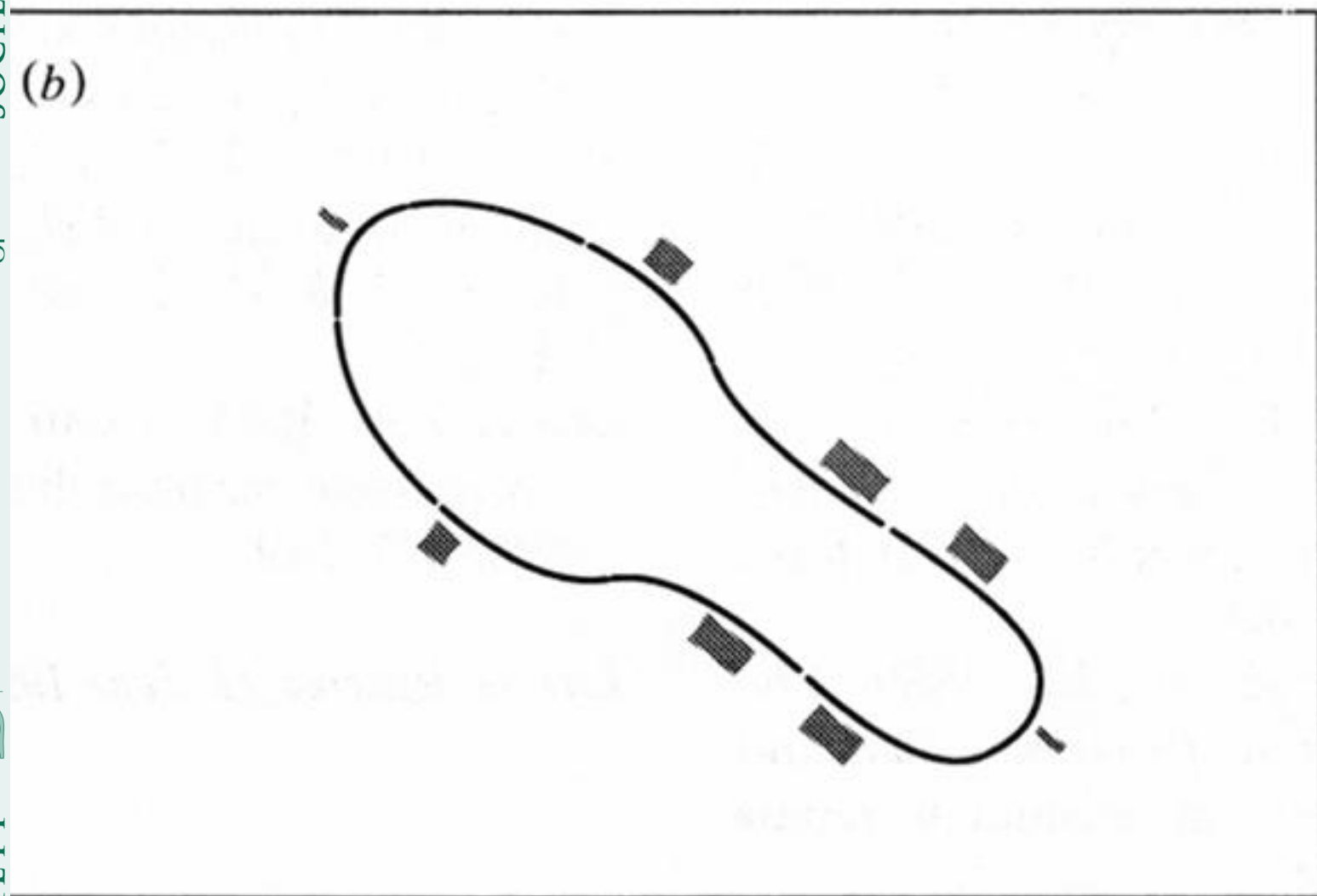
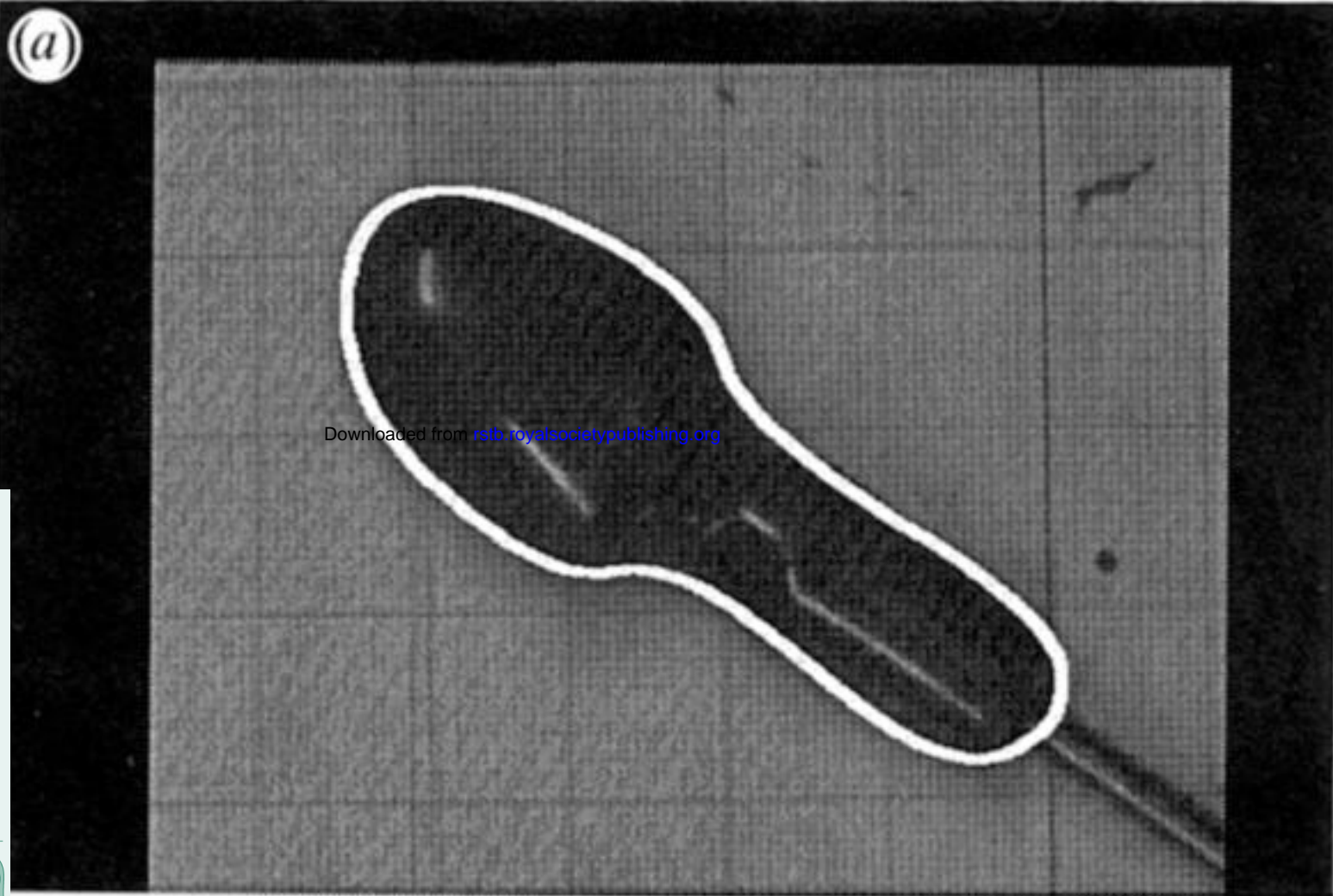


Figure 4. (a) A screwdriver, as seen by the robot's camera, with a 'dynamic contour' locked onto the outline of its handle. (b) There are four seed grasps of type 1 (see figure 1), the most stable of which are the natural grasps across the handle. The other, much less stable but still feasible, is longitudinal.