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Autore	Hertkorn Katharina
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Sommario/riassunto	"Shared Grasping" describes a new approach to shared autonomy for grasping and manipulation tasks to be used in a telepresence system. It is realized with two assistance functionalities, which simplify the grasping, and a user interface, which merges haptic feedback and visual assistance. User studies confirm a reduction in operator workload and an increase in task performance while maintaining a high immersion of the operator into the remote environment when using the assistance functions.