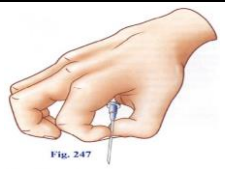
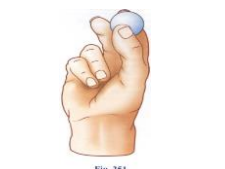


	Grips or Tweezers		Definition	Figure
M1	Bidigital	Prehesion by terminal opposition	The finger 2 and 3 come into contact during opposition at the tips.	
M2		Terminal opposition	The finger 1 and 2 (or any other finger) are in contact on the palmar surfaces of their pulps.	
M3		Opposition prehension by subterminal-lateral	The palmar aspect of the pulp of the thumb presses on the radial surface on the first phalanx of the index	
M4		Interdigital latero-lateral prehension	Occurs between the fingers 2 and 3	
M5	Pluridigital	Tridigital		
		Tridigital	Hold a little ball or loosen a lid	
M6		Tridigital with pulp contact	Hold a spheric item	
M7		Tetradigital with pul and lateral contact	When a larger lid is loosen	
M8		Tetradigital with pulp contact (pulp-tridigital)	Fasten a pencil	
		Pentadigital		
M9		Pentadigital with pulp contact	The palmar surfaces of the fingers 1 to 5 are in contact with object and surround it almost completely	
M10		Pentadigital with pulp to side contact	Bulky items (tennis ball)	
M11		Pentadigital hemi-spherical	The fingers 1 and 2 are widely separated from one another	
M12		Panoramic pentadigital grip	It depends on wide separation of the fingers with the thumb in maximal counteropposition, i.e. adduciton and extension	

M13	Palmares	Digitopalmar	Oppose the hand to last four fingers	 Fig. 262
M14		Hand as a whole	Power-grip	 Fig. 264
M15		Cylindrical palmar	Objects of important diameter	 Fig. 267
M16		Spherical palmar	It can implies three, four or five fingers	 Fig. 269
M17		Pentadigital spherical	The thumb opposes to the ring finger	 Fig. 270
M18	Centered	Orchester director/screwdriver/fork grip	They are in fact symmetrical about a longitudinal axis, which generally coincides with the axis of the forearm	 Fig. 273
M19	Tweezers with gravity	Tweezers with gravity simple	Tray type	 Fig. 275
M20		Tridigital tweezer with gravity	Hold a cup using gravity	 Fig. 277
M21		Tweezer in grip position	Hook type, e.g. holding a suitcase	