For cube on right

Given:

$$\hat{n}_1^N = \begin{bmatrix} 0 \\ 1 \\ 0 \end{bmatrix} \quad \hat{t}_1^N = \begin{bmatrix} -1 \\ 0 \\ 0 \end{bmatrix} \quad \hat{n}_2 = \hat{n}_3 = \begin{bmatrix} 0 \\ -1 \\ 0 \end{bmatrix} \quad \hat{t}_2 = \hat{t}_3 = \begin{bmatrix} 1 \\ 0 \\ 0 \end{bmatrix}$$
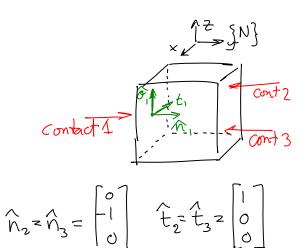
(A) Determine $G \ni$ the contacts could apply any $g \in \mathbb{R}^6$ and could move to cause any $\nu \in \mathbb{R}^6$

(B) Design simple fingers $\ni$ the hand (with contacts determined in (A)) can command any $g \in \mathbb{R}^6$ and $\nu \in \mathbb{R}^6$

(C) Does the grasp have form closure? Why or why not?

(D) Does the grasp have frictional form closure?
Find finger locations and small $\mu > 0$ $\ni$ friction form closure does not exist.

(E) Does the grasp have force closure?
What changes could you make to the system so that your answer would be reversed?