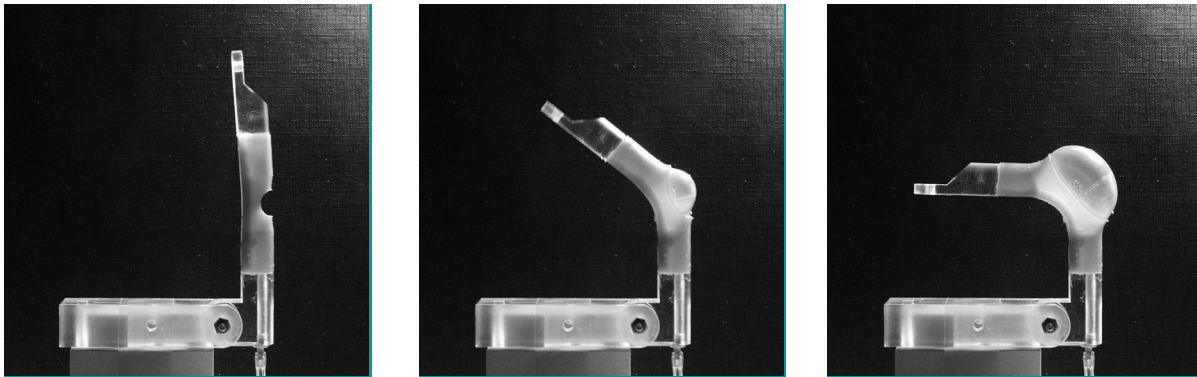


Compliant finger gripper

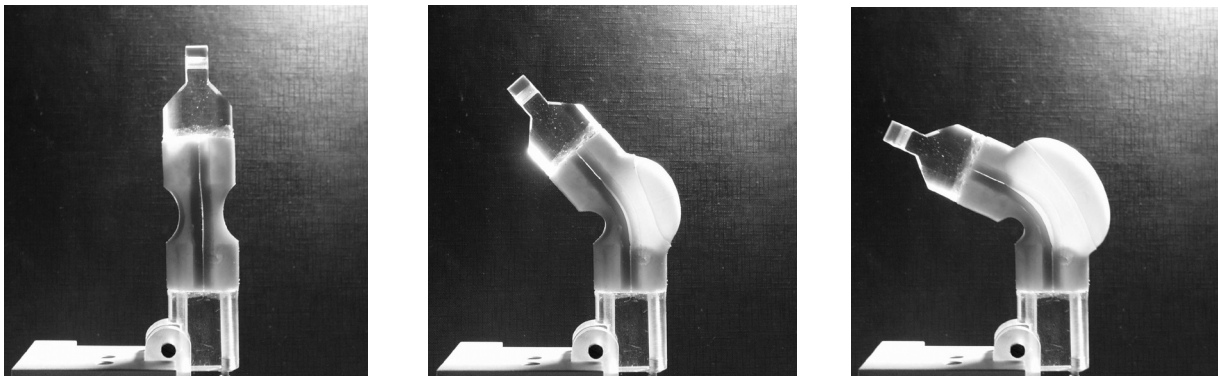
System: Compliant gripper with material coherent joints actuated by a pneumatic drive

Functional principle: Based on the shape of the joint and a special wall thickness a bending deformation of the structure is realized by an internal pneumatic pressure.



Characteristics and advantages:

- local joint area
- highly elastic material
- bending range of 90 degrees of a single gripper finger
- monolithic compliant design of a single finger, produced in one single step
- cascading is possible



Application:

- external and internal gripping by single or cascaded finger
- touch finger
- lever for the force transmission
- legs for a walking robots
- monolithic robot arms

