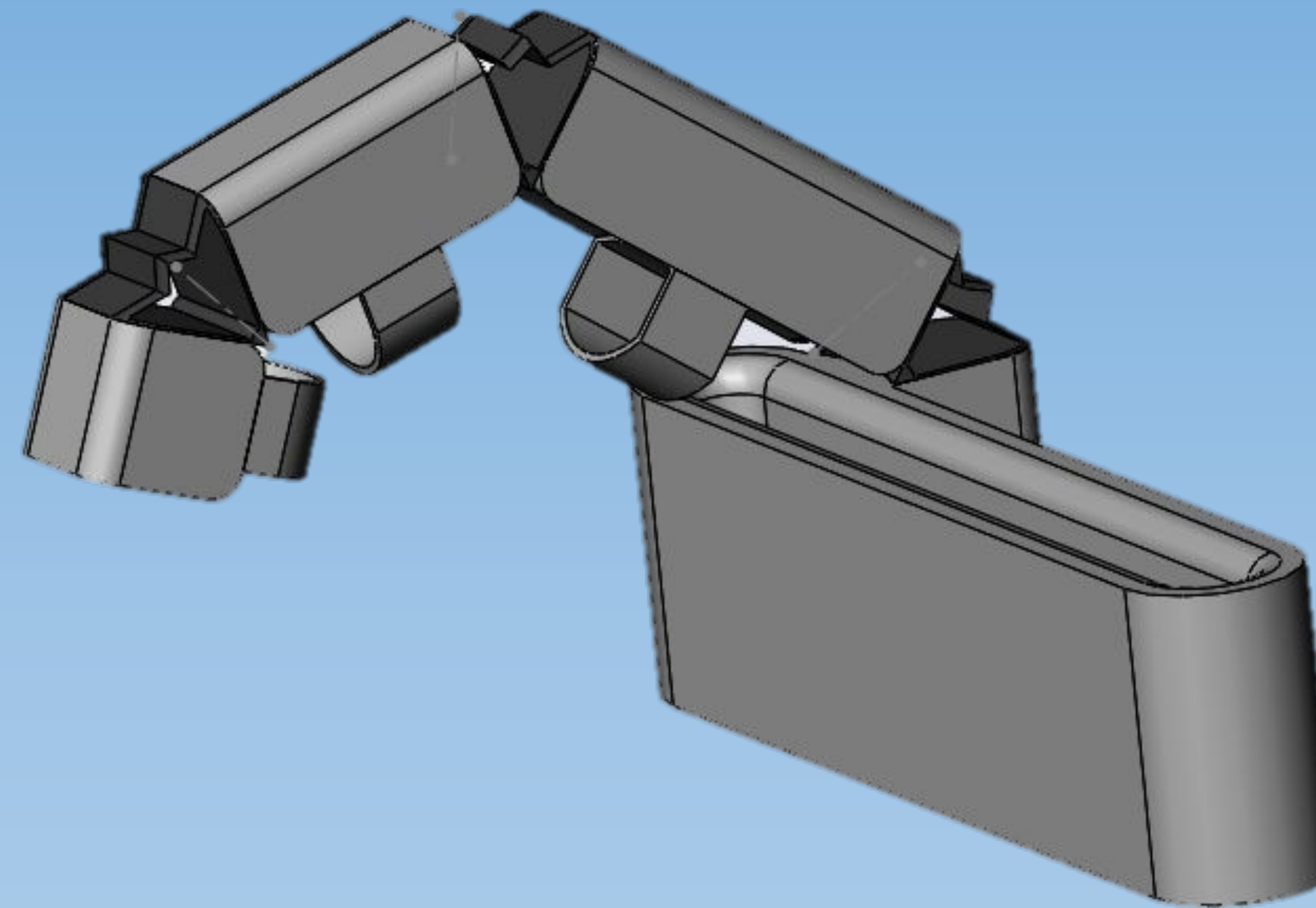


# Soft Robot Finger

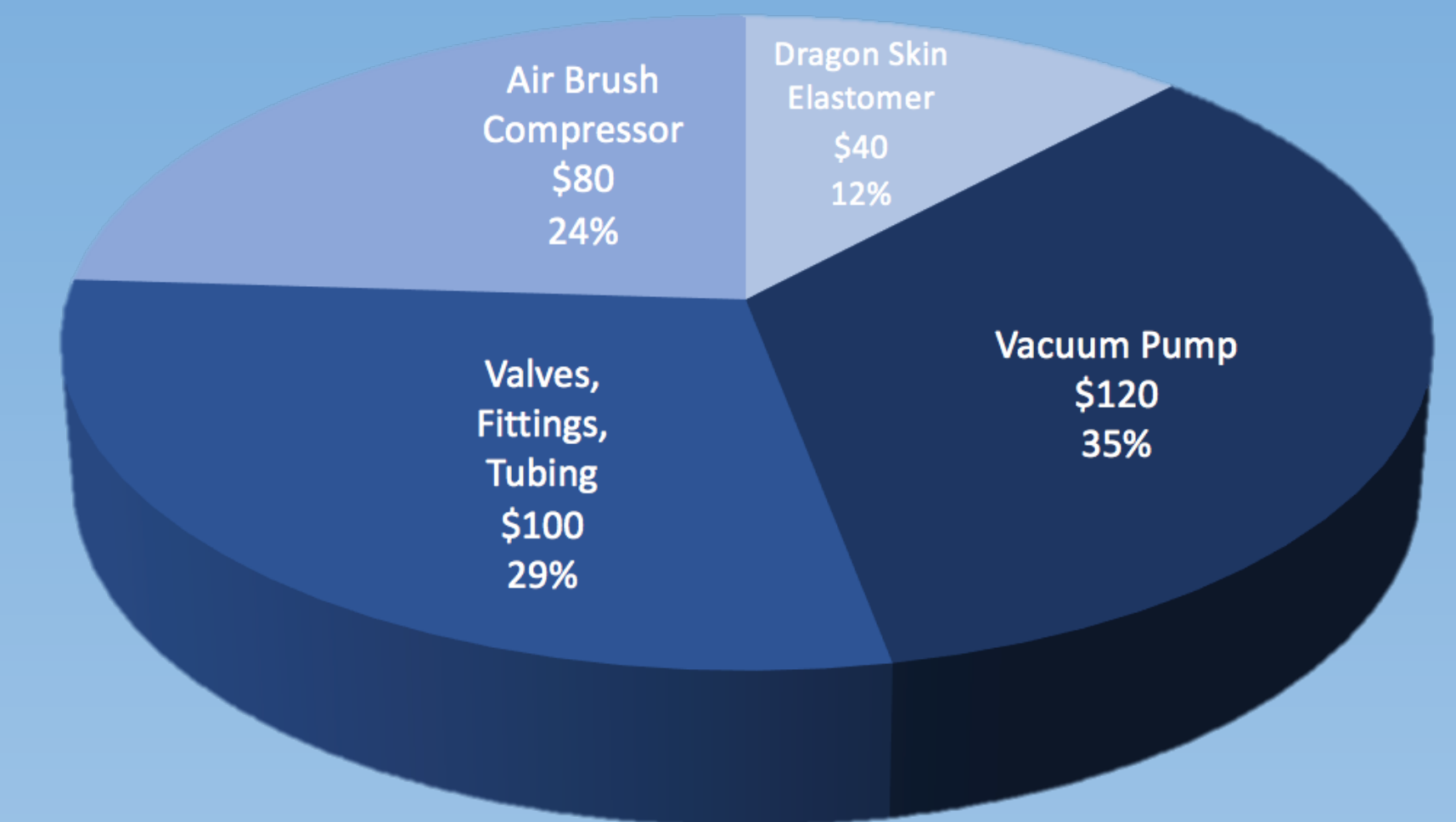
Faculty Advisor: David J. Reinkensmeyer

## Introduction

The purpose of our project is to extend our knowledge on finger locomotion. We hope to gain insight on muscle contractions, and optimize a device to have the ability to restore a patient's paralyzed finger. Further development on the project can extend to full hand rehabilitation.



## Estimated Budget



## Goals and Objectives

Our goals for this project is to construct a device that can help restore motion in a paralyzed finger. We will achieve this by constructing a mold, from which we will cast the device using an elastomer material. With the help of valves, tubing and pumps, the device can be actuated to mimic finger motion.

## Team Members

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## General Timeline

