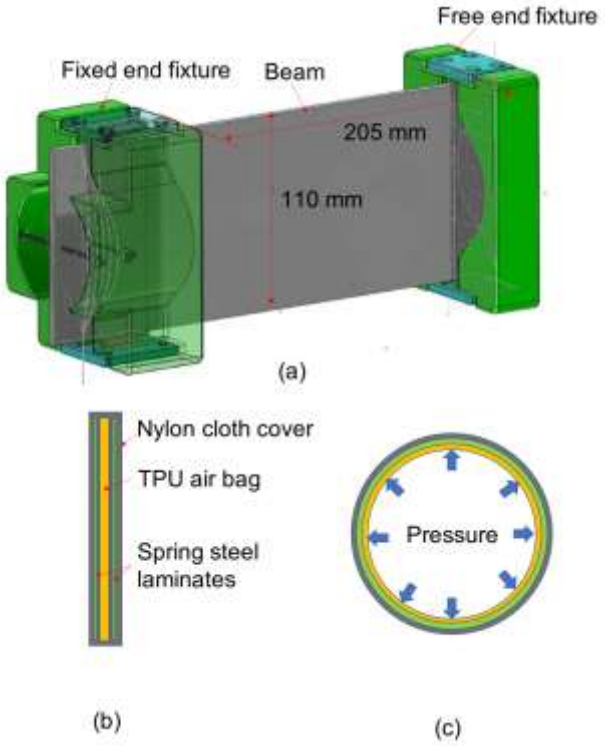
Hybrid Jamming Variable-Stiffness Link for Safe Co-Robots

Yitong Zhou
Shien-Ming Wu School of Intelligent Engineering, South China University of Technology, China
Leon M. Headings and Marcelo J. Dapino
Mechanical and Aerospace Engineering, The Ohio State University, USA

- We propose a tunable stiffness mechanism for co-robot links based on hybrid jamming
- It is made of multiple thin layers of spring steel and cloth, and an air bladder
- Bending stiffness and cross-section area increases with air pressure
- Around 66 times bending stiffness change is achieved (0.26 to 17.42 N/mm)



3D rendering of a hybrid jamming beam