Piede per esoscheletro robotico per la deambulazione assistita di soggetti affetti da deficit locomotori

Matteo Laffranchi, Stefano D’angella, Paolo Uboldi, Jody Saglia, Carlo Sanfilippo

The invention consists in a flexible sensorised footsole for lower limb orthotic/prosthetic devices or humanoid robots. Its purpose is to exploit its flexibility to replicate a more human-like gait, absorb the shock at the impact during the landing phase or deflect during toe-off, or yet deform accordingly with any interaction with the environment or the wearer in case of a wearable robot. The sole is also sensorised to measure the interaction force.

Rehabilitation, humanoid robotics

Footsole, leaf-springs, wearable, robot, sensorised, foot, shock absorber

Sensorized foot for robotic/exoskeleton applications

Matteo Faccenda

+39 010 71781 968