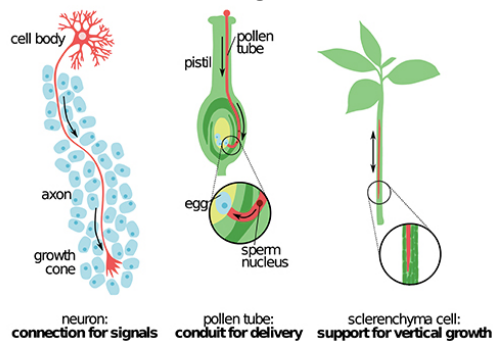


CAREER: Physical Principles and Applications of Plant-Inspired Tip Growth for Robotics

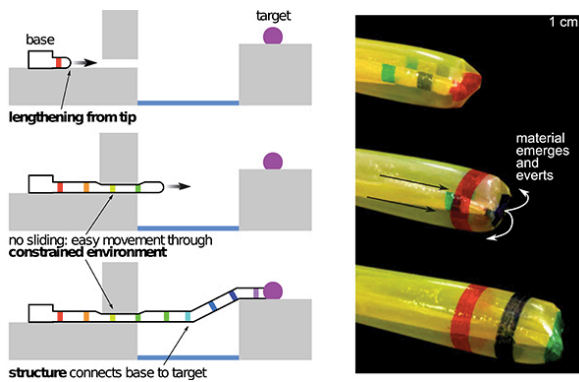
Elliot W. Hawkes (University of California at Santa Barbara)

Concept

Can we leverage the concept of tip growth, found across diverse organisms in nature?



The research objective of this project is to use analytical modeling and hypothesis-driven experimentation to elucidate the physical principles governing the behavior of tip-growing "vine" robots.

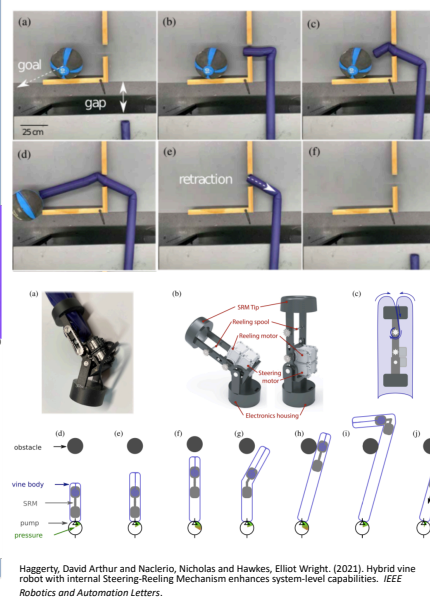


Scientific Impact

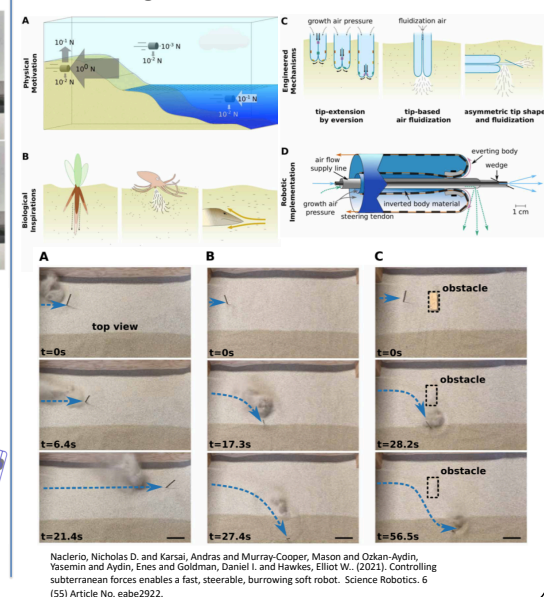
1) Design, Modeling, Control: Organizing Current Knowledge



2) New Methods for Steering and Retraction



3) New Understanding and Applications: Burrowing in Granular Media



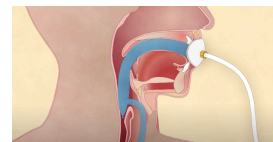
Broader Impact

Developing Remote Soft Robotics Course

We have created fully remote courses with six lab modules for instructing soft robotics at the undergraduate and graduate levels. We have shared the content with an initial group of colleagues for feedback.

Medical Applications

We are developing the understanding and expertise to move easily through the body. The first application area is emergency intubation.



Extreme subterranean mobility

We are developing the understanding and expertise to move below ground. Applications include search and rescue in mudslides as well as deployment of sensors for farming.



Outreach

We created a science outreach video in collaboration with the YouTube Science Channel Veritasium, and has been viewed more than 20 million times!

