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Example, Jurmain Et Al. [11] Designed A Remotely Operated Robot For Bio-event Disaster Response, Called HazBot. It Is Composed Of A Mobile Robot Equipped With A 6-degrees-of-freedom (6-DoF) Manipulator. The Manipulator Incorporates Jan 11th, 2024

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Article. In Both Setups The KUKA/DLR Light-weight Robot (LWR) Was The Main Means Of Both Human Machine Interaction

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An UltraMotion Lead Screw Actuator With An Animatics 1720 DC Motor Was Used In Place Of The Pneumatic Piston In The Original Machine (see Fig. 7). The Motor Drives The Lead Screw Via A Rubber Pulley With Gear Ratio 1:1 Attached To The Shaft. The Angle Of The Motor Is Determined Using A 2000 Feb 19th, 2024

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Standardized Evaluation Of Haptic Rendering Systems

Sensor (Figure 1) (ATI Industrial Automation, Apex, NC, USA). The Reported Spatial Resolution Of The Force Sensor Is As Follows (the Z-axis Is Aligned With The Axis Of The Probe): F_x, F_y 1/320 N; F_z 1/640 N; T_x, T_y 1/128 N·mm; T_z 1/128 N·mm. A Replaceable Sphere-tipped Coordinate Measuring May 4th, 2024

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ATI Industrial Automation, Inc., Apex, NC. C. Phantom Materials For Physiological Tactility To Investigate Materials To Best Mimic Human Tissue For Benchtop Testing Of Our Force-sensing Needle, We Made Phantom Tissues Based On Materials Used In The Literature [24]- [26]. Phantom Tissue Ma May 2th, 2024

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Able Both 3-DOF And 6-DOF Haptic Rendering In The Unreal Engine 4. The Core Is The Combination Of The Integration Of A State-of-the-art Collision Detection Library With Support For Very Fast And Stable Force And Torque Comp Mar 11th, 2024

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