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PDEs Vrushali A. Bokil Bokilv@math.oregonstate.edu And Nathan L. Gibson Gibsonn@math.oregonstate.edu Department Of Mathematics Oregon State University Corvallis, OR DOE Multiscale Summer School June 30, 2007 Multiscale Summer School CE P. 1 Mar 4th, 2024

### **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 5th, 2024

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(3)  $E E L E E V V F R V R R R R^2 = -\pi 2\rho$  (4)  $FC F_b F_d F_f R R R R = + +$  (5) FG: Gravity ( $m_e$  Is The Mass Of E And  $G$  Is The Gravity Acceleration); FL: Ambient Viscous Friction ( $r$  Is The Radius,  $\rho$  Is The Medium Density And  $V$  Is The Velocity); FC: Connection Forces, See Eq. 6. FC F\_b F\_d F\_f R R Feb 8th, 2024

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