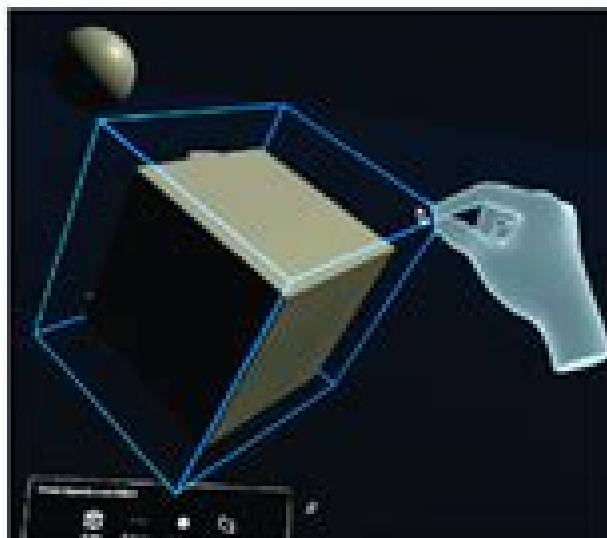


A**Object instantiation****B****Ray-casting-based interaction****C****Object scaling****D****Collision-based interaction**

Haptic Rendering Techniques For Non Physical Command Decision Support

Dangxiao Wang, Jing Xiao, Yuru Zhang



Haptic Rendering Techniques For Non Physical Command Decision Support:

Haptic Rendering Techniques for Non-Physical, Command Decision Support, 2004 Haptic Rendering for Simulation of Fine Manipulation Dangxiao Wang, Jing Xiao, Yuru Zhang, 2014-10-17 This book introduces the latest progress in six degrees of freedom 6 DoF haptic rendering with the focus on a new approach for simulating force torque feedback in performing tasks that require dexterous manipulation skills One of the major challenges in 6 DoF haptic rendering is to resolve the conflict between high speed and high fidelity requirements especially in simulating a tool interacting with both rigid and deformable objects in a narrow space and with fine features The book presents a configuration based optimization approach to tackle this challenge Addressing a key issue in many VR based simulation systems the book will be of particular interest to researchers and professionals in the areas of surgical simulation rehabilitation virtual assembly and inspection and maintenance

Real-time Haptic Interaction with Remote Environments Using Non-contact Sensors O. Fredrik Rydén, 2013 Haptic interaction with a haptic device has traditionally been limited to interaction with purely virtual objects or to static range scans of physical objects Haptic interaction with physical objects at a distance has not been possible without the use of a remote contact manipulator This dissertation describes methods and algorithms for real time haptic interaction with remote environments using non contact sensors remote touch A method of rendering 3 DOF degree of freedom force feedback of streaming point cloud data from a combined range video sensor is presented This is further combined with a novel method for increasing the robustness in interaction with moving physical that is also evaluated These methods are then extended to demonstrate that forbidden region virtual fixtures for telemanipulation can be rendered by extending the concept of remote touch to rendering of haptic virtual fixtures Both of these methods are then extended to 6 DOF haptic interaction with force as well as torque feedback The presented methods of remote touch rendering and virtual fixture rendering were validated by implementation on commercially available hardware The methods for remote touch successfully renders force feedback at 1000 Hz based on the user s interaction with the streaming point cloud data The methods for rendering of virtual fixtures are first demonstrated to protect an isolated beating heart using a forbidden region virtual fixture and then to keep the user away from as well as guide the user to underwater valves

An Implicit-based Haptic Rendering Technique Laehyun Kim, 2003 Haptic Rendering Ming C. Lin, Miguel A. Otaduy, 2008 Human Perception of Kinesthetic Haptic Renderings and Applications in Medical Teleoperation Bolun Zhang (Ph.D.), 2024 There has been significant progress in haptic technology including the development of advanced devices and sophisticated rendering algorithms This progress is driven by a wide range of applications such as simulating the real world in virtual reality aiding in rehabilitation facilitating the communication of signals and teleoperation Despite these advancements much remains unknown about how haptic devices perform in specific application contexts and how to improve the performances Evaluating the performance of haptic devices involves not only engineering metrics but also user perception As a result user studies

have become an essential tool in this field Psychophysical methods which examine the relationships between physical stimuli and sensory perception have also been applied to haptics to gain deeper insights Human perception of haptic feedback can be broadly categorized into two modalities kinesthetic and tactile though the distinction is not always clear cut Kinesthetic feedback involves sensations of force and motion and devices targeting this modality include exoskeletons and force feedback systems that simulate physical interactions with virtual objects Tactile feedback on the other hand involves sensations felt through the skin such as vibrations pressure temperature and texture Devices focusing on this modality include vibration motors and electrotactile systems that create the sensation of touch on the user s skin Recently beyond merely pushing the boundaries of performance several techniques such as sensory substitution and sensory augmentation have been developed to enhance the effectiveness of haptic devices involving both modalities These advancements have led to more immersive and effective applications across various fields This thesis studies how haptic rendering techniques perform in specific contexts First we investigate kinesthetic feedback examining how rendering elements affect perception This involves exploring how people perceive categorize linear impedances as well as evaluating how rendering parameter accuracy affects user s perceived realism Next we apply these findings to a specific context in teleoperation exploring how techniques can be used to improve perception involving both kinesthetic and tactile modalities By integrating both types of feedback we aim to enhance the overall user experience and performance in teleoperated systems making remote operations more intuitive and effective

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