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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): Fx,Fy 1/320 N; Fz 1/640 N; Tx,Ty 1/128 N·mm; Tz 1/128 N·mm. A Replaceable Sphere-tipped Coordinate Measuring Feb 8th, 2024

Multi-Finger Haptic Rendering Of Deformable Objects

(3) E E L E E V V F R V R R R R2 = $-\Pi$ 2 ρ (4) FC Fb Fd Ff R R R R = + + (5) FG: Gravity (me Is The Mass Of E And G Is The Gravity Acceleration); FL: Ambient Viscous Friction (r Is The Radius, ρ Is The Medium Density And V Is The Velocity); FC: Connection Forces, See Eq. 6. FC Fb Fd Ff R R Jun 1th, 2024

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