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User. 4.2 The Virtual Environment In This Project, We Created A Virtual Environment To Simulate Diffusion Across The Cell Membrane And A Concentration Gradient For Particles At Cellular Level (Fig. 2). In This Virtual Environment, The Planar Object Dividing The World Into Two Halves Represents The Cell Membrane. The Texture Of This Object Depicts The Lipid Bilayer Which Is The Building Blocks ... Jan 3th, 2024

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But The Authors Have Not Implemented The Edition Of Motion Effects. Park Et Al. Also Described An Editor Based On MPEG-V Which Seems To Support The Creation Of Motion Effects [3]. The Creator Has To Manually Specify The Direction Of The Movement And The Value Of The Acceleration Or Speed. The Edition Of Motion Effect Is Discussed By Shin Et Al. Who Jun 1th, 2024

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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 Jun 3th, 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 And Training. The LWR Is A Revolute Joint Robot, With Integrated Electronics Comprising Torque And Position Sensors [8]. This Sensory Equipment Enables Compliant Behavior Feb 4th, 2024

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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 Jul 3th, 2024

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Characterization Of Real-time Haptic Feedback From Multimodal Neural Network-based Force Estimates During Teleoperation Zonghe Chua 1, Student Member, IEEE And Allison M. Okamura ; Fellow, Jul 2th, 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 Apr 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 Mar 3th, 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 Col-lision Detection Library With Support For Very Fast And Stable Force And Torque Comp Mar 1th, 2024

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Typical Acceleration As A Function Of Input Voltage
With 100 G Load. May 3th, 2024

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