

Title (en)
TELESURGICAL SYSTEM WITH INTRINSIC HAPTIC FEEDBACK BY DYNAMIC CHARACTERISTIC LINE ADAPTATION FOR GRIPPING FORCE AND END EFFECTOR COORDINATES

Title (de)
TELEOPERATIONSSYSTEM MIT INTRINSISCHEM HAPTISCHEN FEEDBACK DURCH DYNAMISCHE KENNLINIENANPASSUNG FÜR GREIFKRAFT UND ENDEFFEKTORKOORDINATEN

Title (fr)
SYSTÈME DE TÉLÉOPÉRATION À RETOUR DE FORCE HAPTIQUE INTRINSÈQUE PAR ADAPTATION DYNAMIQUE DES CARACTÉRISTIQUES DE LA FORCE DE PRÉHENSION ET DES COORDONNÉES DE L'EFFECTEUR TERMINAL

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Application
EP 16703921 A 20160118

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Abstract (en)
[origin: WO2016120110A1] The invention relates to a telesurgical system comprising: - a slave, which has a drive unit driving a gripping end effector, a kinematic coordinate of the end effector and a gripping force Feffector being determinable, - a camera, preferably integrated into the slave and being oriented towards the end effector, and - a master, which is remotely connected to the slave, having at least one control unit on which an user can exert a gripping force FG, said gripping force being transmitted to the slave, and having a visual user interface representing the image of the camera, with the proviso that FG is linearly dependent on the kinematic coordinate and Feffector.

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Citation (search report)
See references of WO 2016120110A1

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