

A close-up, slightly low-angle shot of the Pepper robot's head and upper torso. The robot is white with a smooth, rounded design. Its eyes are large, circular, and glowing with a bright blue light. It has a small, dark, curved line for a mouth, giving it a friendly expression. The background is a plain, light blue gradient.

VOORTGANG ONDERZOEK PEPPER

Een onderzoek naar de mogelijkheden van
robot Pepper

Team Pepper



Inhoud

Bezoek manueel therapeut LUMC
Verandering doel onderzoek
Kinect vs Realsense
Libraries en SDK's
Volgende stappen...

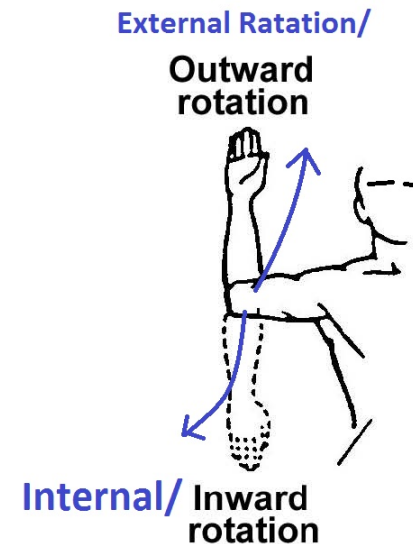
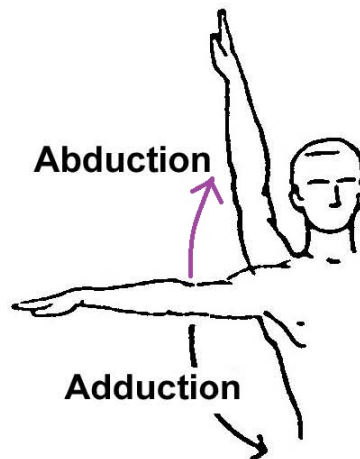
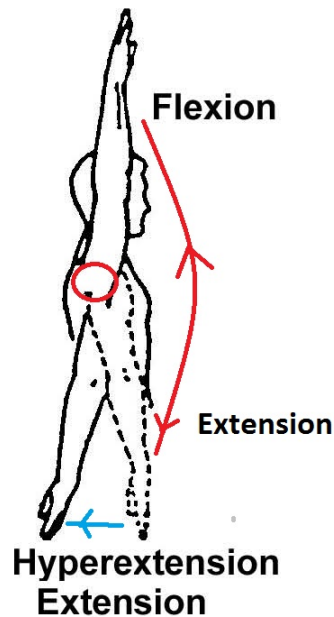
Bezoek manueel therapeut LUMC

- Functiestoornissen gewrichten
- Actief vs. Passief bewegen
- Oefeningen om 'painfull arcs' te meten

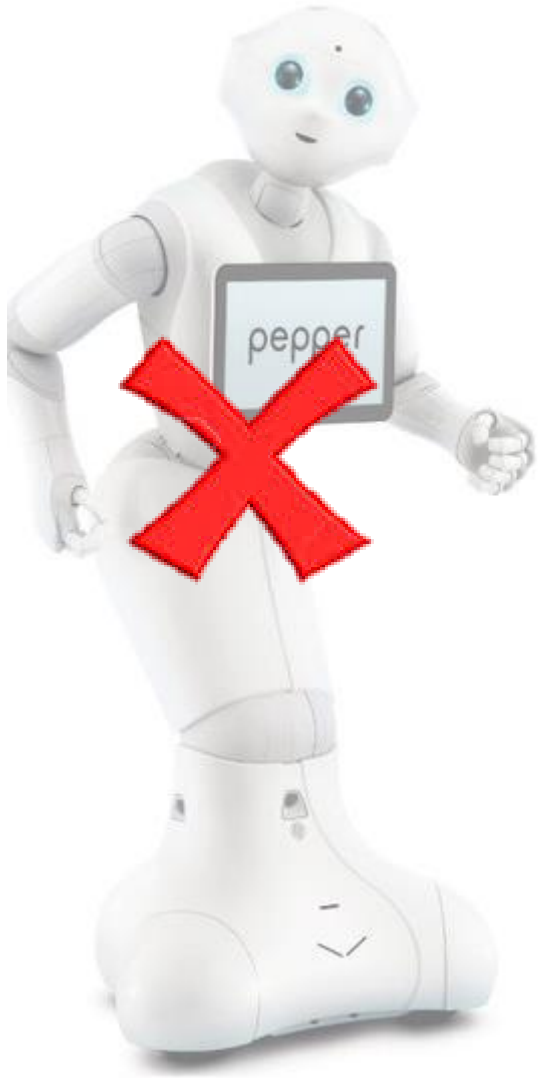


Bezoek manueel therapeut LUMC

- Welke oefeningen?



Verandering doel onderzoek



Kinect vs. RealSense

- We gaan dus de kinect gebruiken!
- Waarom?
 - Ondersteuning van software
 - Kinect SDK bevat skeleton tracking algoritme
 - Goedkoop om aan te schaffen
 - Andere onderzoeken gebruiken ook de Kinect
 - Kinect: goede nauwkeurigheid

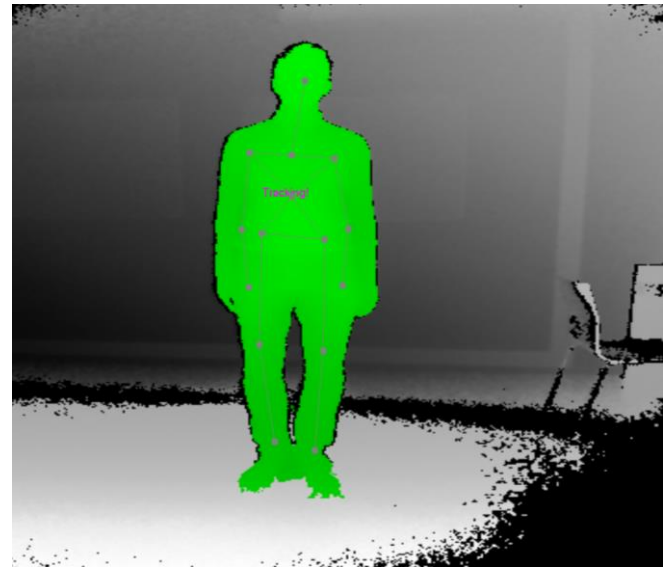
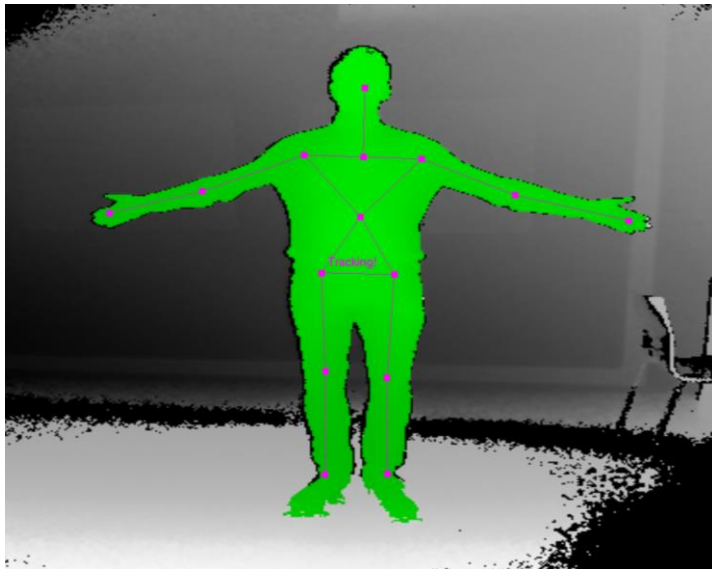
Discontinuation Notice

The Intel® RealSense™ SDK for Windows*, the SDK components, and depth camera managers for the F200, SR300, and R200 versions will no longer be updated. You may continue to use the SDK with limited support, or use the Intel® RealSense™ Cross Platform API for camera access, and then develop on other platforms via [GitHub*](#).

For the Intel® RealSense™ SDK 2.0—our next generation SDK—support will only be available for Intel® RealSense™ cameras SR300 and D400-Series through GitHub.

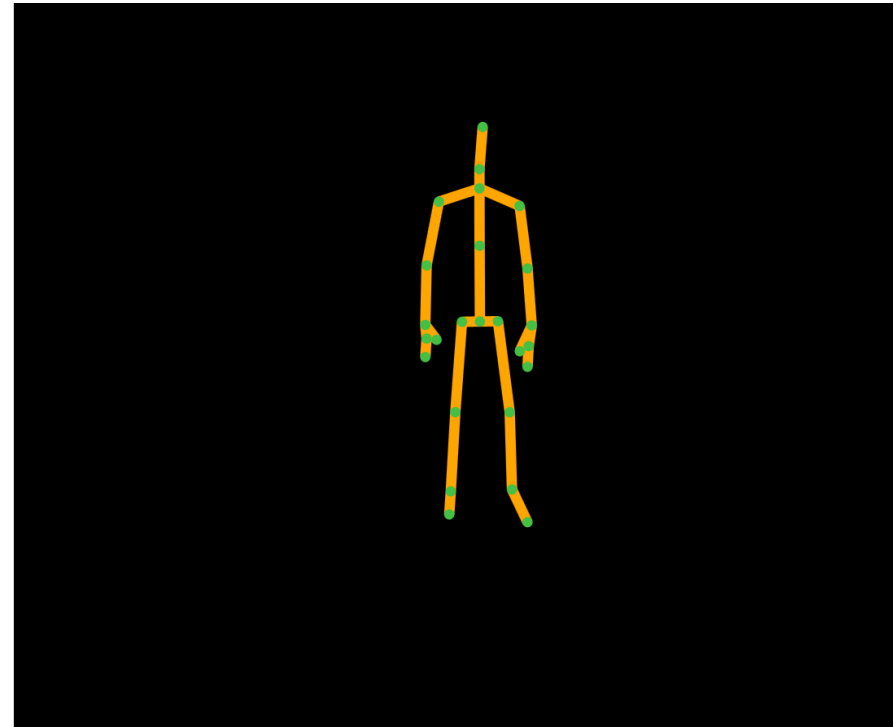
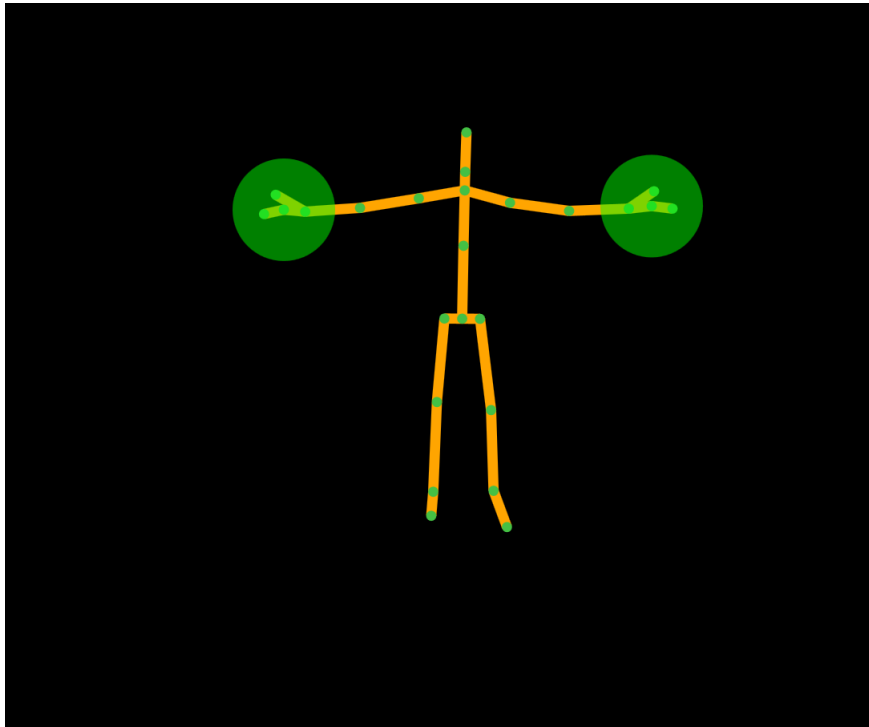
Libraries en SDK's

- Freenect, OpenNi2, NITE
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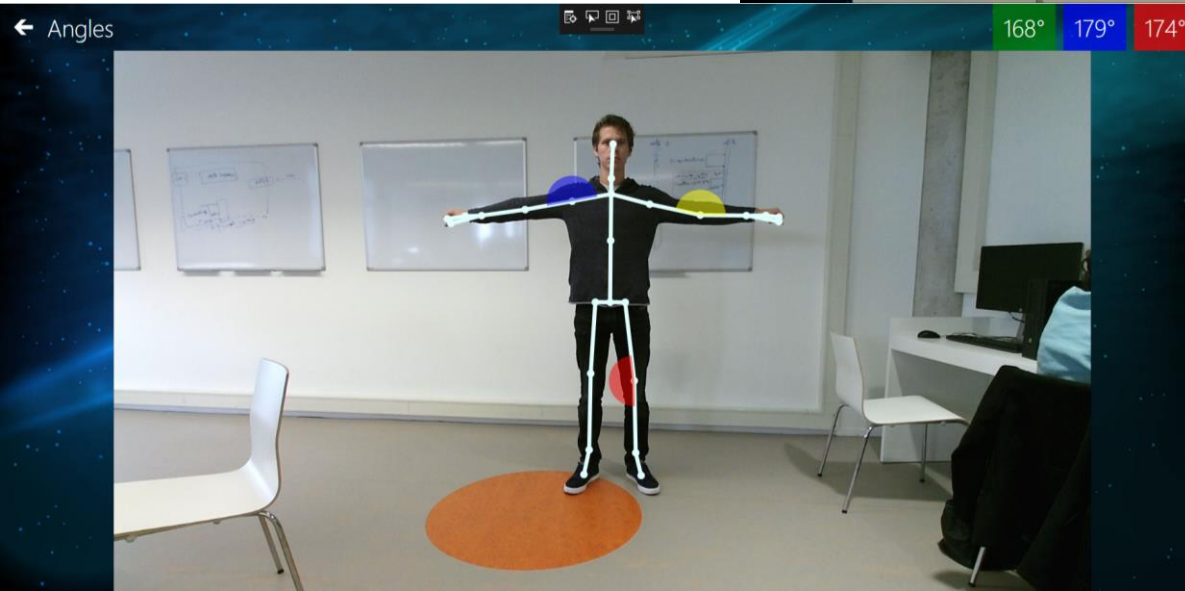
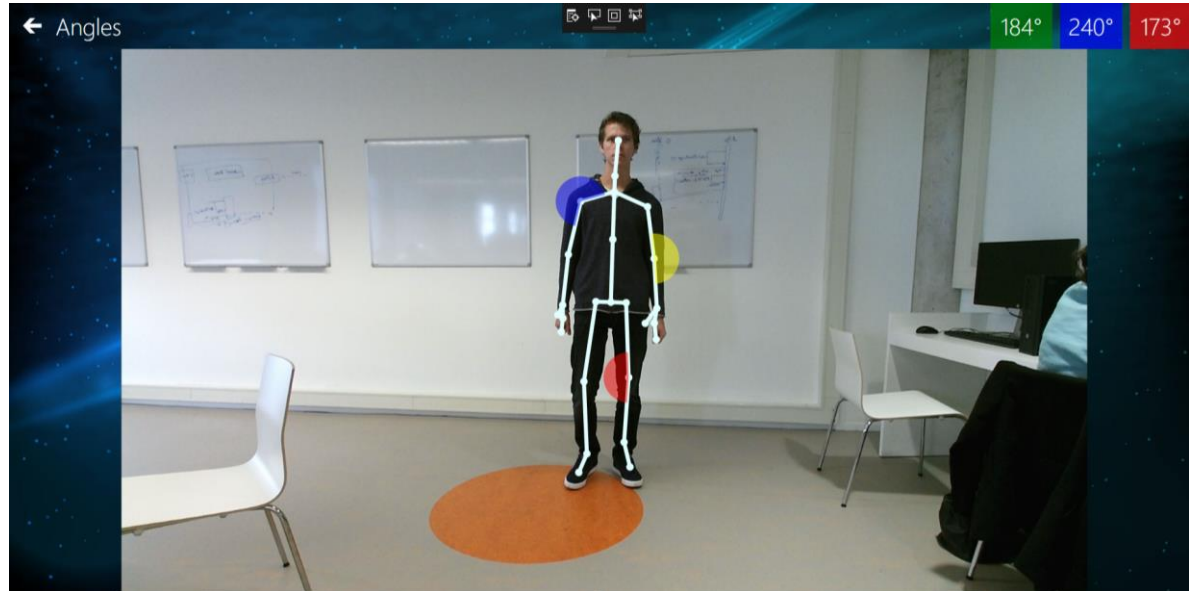
Libraries en SDK's

- Windows SDK



Libraries en SDK's

- Vitruvius



Volgende stappen...

- Vaststellen welke data we uit de beelden moeten halen
- Data opslaan van de camera
- Hoeken/ orientatie meten van de gewrichten

Vragen?

