Some additional information is below:

* The skill breakdown of the data is:
* Experts: 149, 151, 184
* Novices: 188, 190, 196, 198
* Each task comes with 3 types of simultaneously recorded kinematic data files:
* \_SI.mat: kinematic data from the Si robot
* \_SSC.mat: kinematic data from the Surgeon-Side Console
* \_EVT.mat: list of system events from both SSC and SI
* Pose data: position and orientation of an instruments in a length-12 vector
* x,y,z values are in meters and are in indices 4,8,12, and rotation (3x3 rotation matrix) are in remainder of the vector.
* Any pose is given with respect to a coordinate system, known as the “reference frame” aka “ref frame.” Pose of main instruments (PSMs) are in ECM tip ref frame, i.e. camera point of view is the origin. The camera may occasionally move during a task, as a result you may see sudden discontinuities in the pose stream.
* “RCM” pose refers to the access ports on the abdominal wall – these won’t move during surgery, feel free to ignore.
* Joint Angle data: angles for each joint in a robotic arm, in radians
* PSMs and ECM each has a few Setup Joints (SUJ): these won’t move during surgery, feel free to ignore.
* Time stamps: \_SI.mat and \_SSC.mat are sampled at about 50Hz. \_EVT.mat is sampled whenever an event occurs and does not have a regular time interval. If you need to read the relative time stamps (in milliseconds): only use the .header.timestamp, not .data.timestamp
* There may be two Surgeon-Side Consoles connected to the robot: as a result 4 MTMs are recorded in each MTM-related data vector: [1L; 1R; 2L; 2R]. The motion of MTM is largely duplicated by the PSM motion, but if you do decide to look into MTM motion, be aware that it may show up in any 2 of the 4 MTM channels.