

.

---

## The four Ws'

Please make a new document for each topic, so it will be easy to edit if there is a mistake.

- Who are you addressing:  
scientists who are specialists in your field of research, a wider group of scientists, fellow students, or public audiences?
  - Why is your message important?  
Why are you communicating it? Presumably you are not doing it just for credits, but to add to the pool of knowledge
  - What are your main findings or “take-home” messages? '  
What are you going to present - new research results or a review of a topic? What prior knowledge, expectations and questions might your audience have? What technical language do they understand?
  - How can you best deliver your message and satisfy the audience's need?  
How will the audience use its new knowledge?
-

## **Test template**

Use this template when you need to make a test of something

**Purpose:**

**Test equipment:**

**Procedure:**

**Measuring data:**

**Results:**

**Uncertainties of measurement:**

**Conclusion:**

---

# Contents

---

<b>1</b>	<b>System overview</b>	<b>1</b>
1.1	Geomagic touch . . . . .	1
1.2	Communication computer . . . . .	2
1.3	Test setup . . . . .	2
1.4	Communication computer . . . . .	2
1.5	Endowrist . . . . .	2
<b>2</b>	<b>Kinematic for the Geomagic touch</b>	<b>3</b>
	<b>Bibliography</b>	<b>5</b>

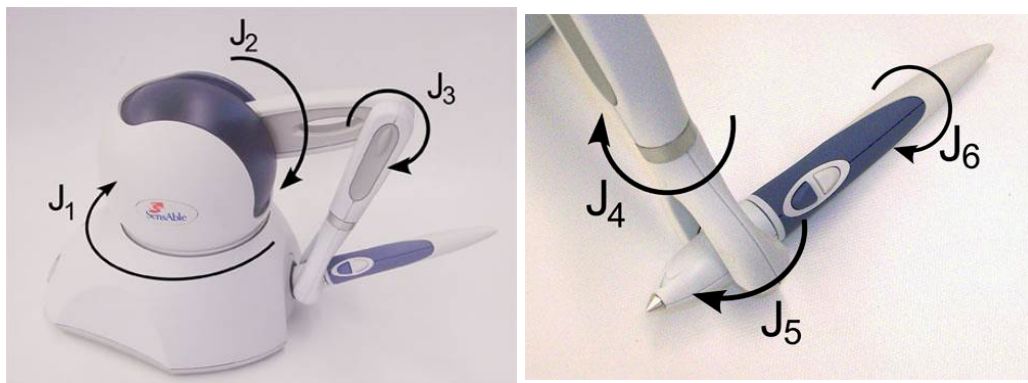
---

In this chapter an description of the system is made. This is made for the reader to get a better understanding of the setup which where available on Aalborg university. This description includes the following points and will be described in the same order

- The Gemagic touch,
- The computer forcommunication,
- The test setup,
- and the Da vinci robot.

## 1.1 Geomagic touch

The geomagic touch is a haptic feedback device, which has the ability to manipulates its joint in such a way that the user feels resistance when moving the pin in a certain direction or way. The geomagic touch described in this section is the model Phantom omni and can be seen on *Figure 1.2*.



(a) Overview of the Phantom omni's first three joints. (b) Overview of the Phantom omni's last three joint

Figure 1.1: Overview of all the Phantom omni's joints[1]

As mentioned the Phantom omni has the ability to generate resistance for the user. In other words, when moved in a specific direction it can create a counter force in respect to a certain position. On *Figure 1.2*, it can be seen that the omni has six degrees of freedom (DOF), where the first three has actuators. This means that the device only has the ability to generate force feedback with three DOF, in this case roll, pitch and yaw.

The connection to the omni can either be made directly through a ethernet cabel or through ethernet cabel to a usb converter into a computer. For programming the omni an API is included, which enables the connection to the omni. The programming of the omni happens through the languages C++.

include  
other  
languages

## 1.2 Communication computer

## 1.3 Test setup

## 1.4 Communication computer

## 1.5 Endowrist

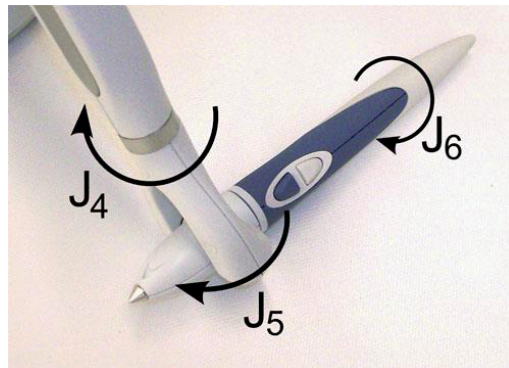
An Endowrist is a surgical tool which can be manipulated as a human wrist. It is used in surgical procedures such as Laparoscopic surgeries, better known as minimally invasive surgery (MIS), where small incisions in the human body is made under the surgery. Because the incision cuts are small, blood lose under the surgery and the risk of infection is reduced. This has a positive effect on the recovery time for the patient.

As mentioned the Endowrist has the ability to be manipulated as a human wrist and thereby has four DOF, see

four  
right?



(a) An Endowrist.



(b) Overview of the Phantom omni's last three joint

Figure 1.2: Overview of all the Phantom omni's joints[1]







# Bibliography

---

- [1] Sigverse, "Using phantom omni haptik device," 2014. Downloadet: 21-10-2016.