**NRI-CSA User Study Steps/Script**

**Before User Arrives**

* Attach ablation phantom
* Start magnetic tracking
* Start robot on matlab computer
  + Get unbias script for force sensor ready
* Run robot (rosrun dvrk\_robot dvrk\_console\_json -j …
* Run vision (roslaunch dvrk\_vision irep….
* Run IREPControl.py

**User Arrives**

* Consent form
* Pre-Experiment Questionnaire
* Free play – let the user control the robot with no haptic feedback

**Ablation Experiment**

**User Modes: ­­­\_\_\_\_\_\_\_\_\_\_ \_\_\_\_\_\_\_\_\_\_\_\_ \_\_\_\_\_\_\_\_\_\_\_\_\_\_ \_\_\_\_\_\_\_\_\_\_\_\_\_\_**

* Mode 2
* User TLX
* Mode 3
* User TLX
* Mode 4/5
* User TLX

**String Experiment**

**User Modes: ­­­\_\_\_\_\_\_\_\_\_\_ \_\_\_\_\_\_\_\_\_\_\_\_ \_\_\_\_\_\_\_\_\_\_\_\_\_\_ \_\_\_\_\_\_\_\_\_\_\_\_\_\_**

* **Unbiased force sensor**
* Mode 6
* User TLX
* Mode 7
* User TLX
* Mode 8
* User TLX

**Wrapping up**

* User finishes TLX survey with open-ended questions