



Haptics For Teleoperated Surgical Robotic Systems (New Frontiers in Robotics)

M. Tavakoli

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An important obstacle in Minimally Invasive Surgery (MIS) is the significant degradation of haptic feedback (sensation of touch) to the surgeon about surgical instrument s interaction with tissue. This monograph is concerned with devices and methods required for incorporating haptic feedback in master-slave robotic MIS systems. In terms of devices, novel mechanisms are designed including a surgical end-effector (slave) with full force sensing capabilities and a surgeon-robot interface (master) with full force feedback capabilities. Using the master-slave system, various haptic teleoperation control schemes are compared in terms of stability and performance, and passivity-based time delay compensation for haptic teleoperation over a long distance is investigated. The monograph also compares haptic feedback with visual feedback and with substitution for haptic feedback by other sensory cues in terms of surgical task performance.

Contents: Introduction; Sensorized Surgical Effector (Slave); Haptic User Interface (Master); Unilateral Teleoperation Control; Bilateral Teleoperation Control; Substitution for Haptic Feedback: Bilateral Teleoperation Control Under Time Delay.

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