

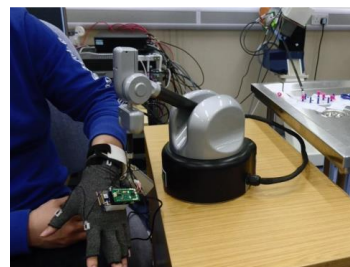
PRESS RELEASE

SMARTsurg Trials

The setup

We would like to present you the trials, executed at SMARTsurg system. The following images present the setup, where some changes were made from the initial plans, mostly from a usability perspective. Most notably all IMU sensors and Arduino were mounted onto a glove, which maintained accurate results, whilst making setup and testing much easier reduced damage to the kit.

No cameras were used, but instead the user was positioned adjacent to the worktable with a good view of the dexterity tests. His body and arm were positioned facing the same way as the Kuka, such that left/right arm motions are matched by the robot, and not mirrored as they would be if the user were facing the robot. The Da Vinci pincer tool was used for all tests.



The Task

The "pick and place" task was carried out, with the user being asked to place 6 rings onto 6 pegs. The user was timed to complete the task, with the times of individual ring placements also being recorded.



The Results

Watch a trial through our Youtube video by clicking on the image or [here](#).





Further details could be found on the project website: <https://smartsurg-project.eu/>

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