



US 20130342451A1

(19) **United States**
(12) **Patent Application Publication**
Berkley et al.

(10) **Pub. No.: US 2013/0342451 A1**
(43) **Pub. Date: Dec. 26, 2013**

(54) **METHODS, APPARATUS, AND ARTICLE FOR FORCE FEEDBACK BASED ON TENSION CONTROL AND TRACKING THROUGH CABLES**

continuation of application No. 11/947,398, filed on Nov. 29, 2007, now Pat. No. 8,054,289.

(60) Provisional application No. 60/868,318, filed on Dec. 1, 2006.

(71) Applicant: **Mimic Technologies, Inc.**, Seattle, WA (US)

Publication Classification

(72) Inventors: **Jeffrey J. Berkley**, Seattle, WA (US);
Seahak Kim, Seoul (KR)

(51) **Int. Cl.**
G06F 3/01 (2006.01)

(73) Assignee: **Mimic Technologies, Inc.**, Seattle, WA (US)

(52) **U.S. Cl.**
CPC **G06F 3/016** (2013.01)
USPC **345/156**

(21) Appl. No.: **14/010,178**

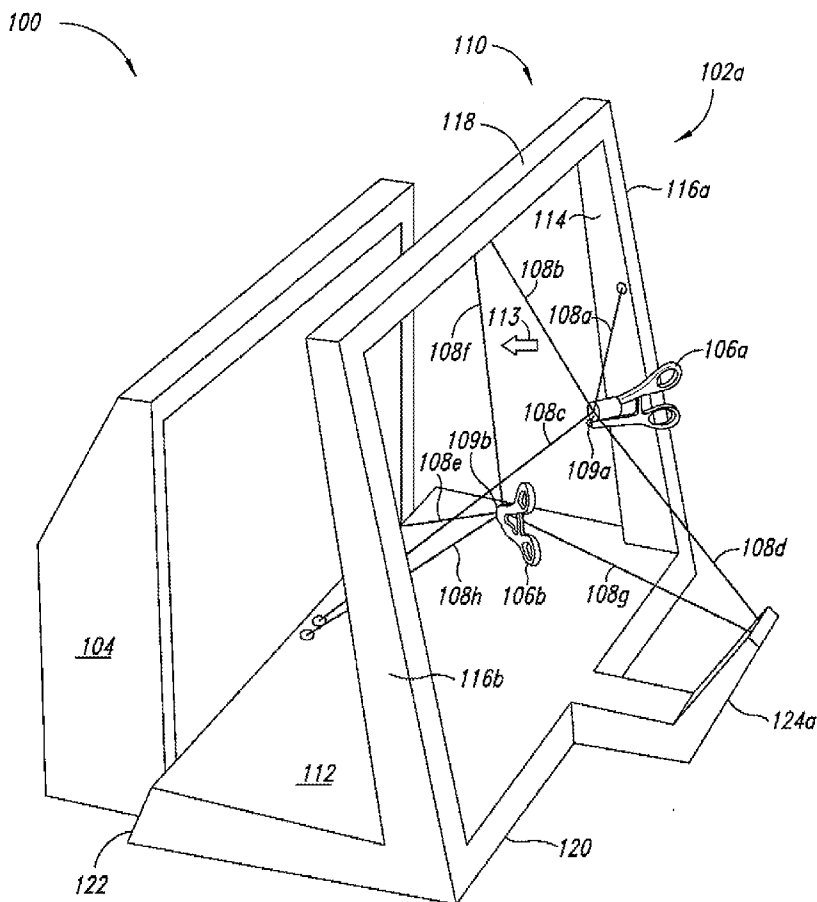
(57) **ABSTRACT**

(22) Filed: **Aug. 26, 2013**

A haptic interface system includes a cable based haptic interface device and a controller. The controller receives information related to movement of a grip in real-space and generates a stereoscopic output for a display device. The stereoscopic output includes images of a virtual reality tool whose motions mimic motions of the real-space grip.

Related U.S. Application Data

(63) Continuation of application No. 13/242,869, filed on Sep. 23, 2011, now Pat. No. 8,547,328, which is a



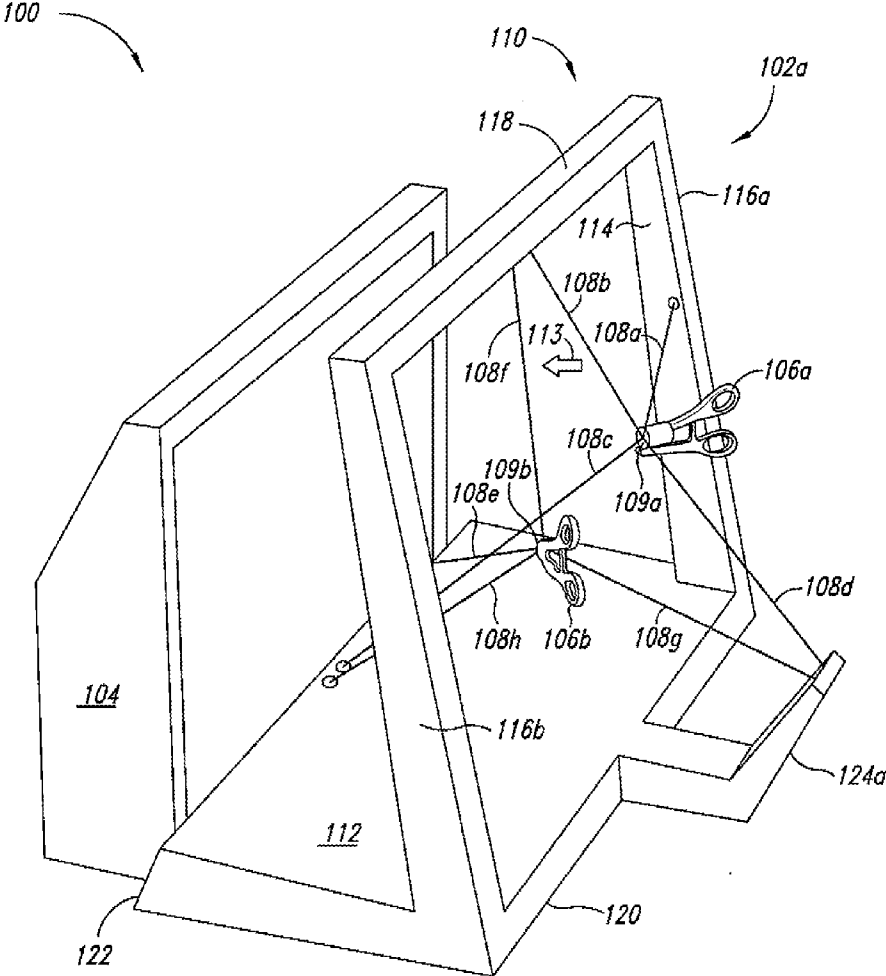


FIG. 1

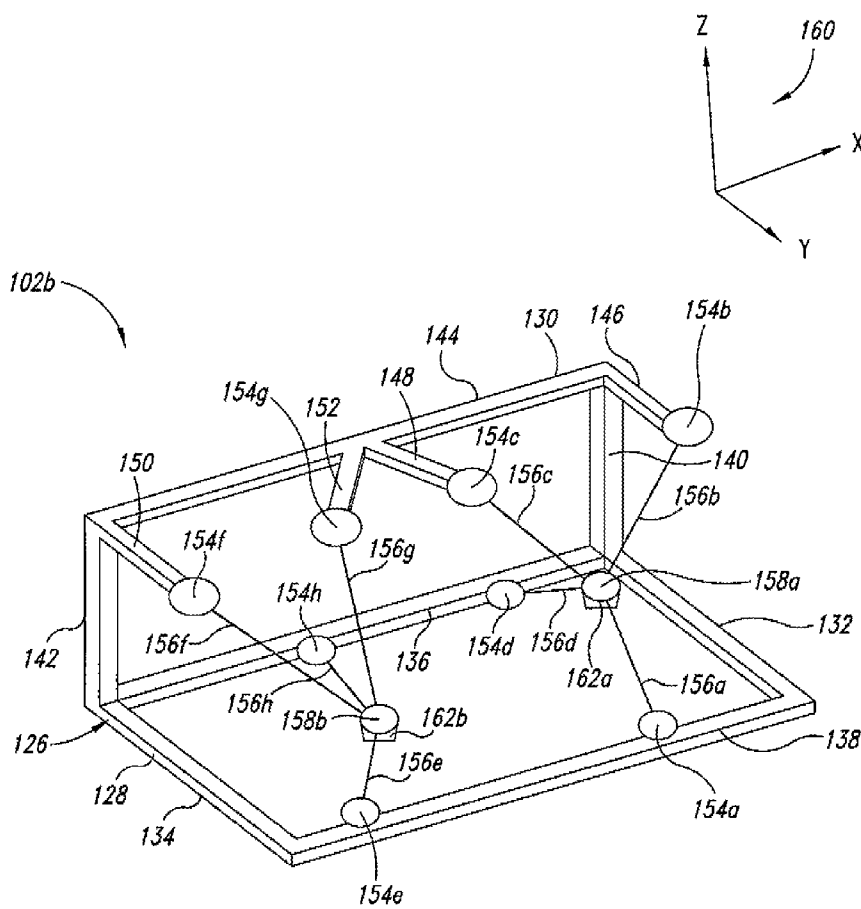


FIG. 2

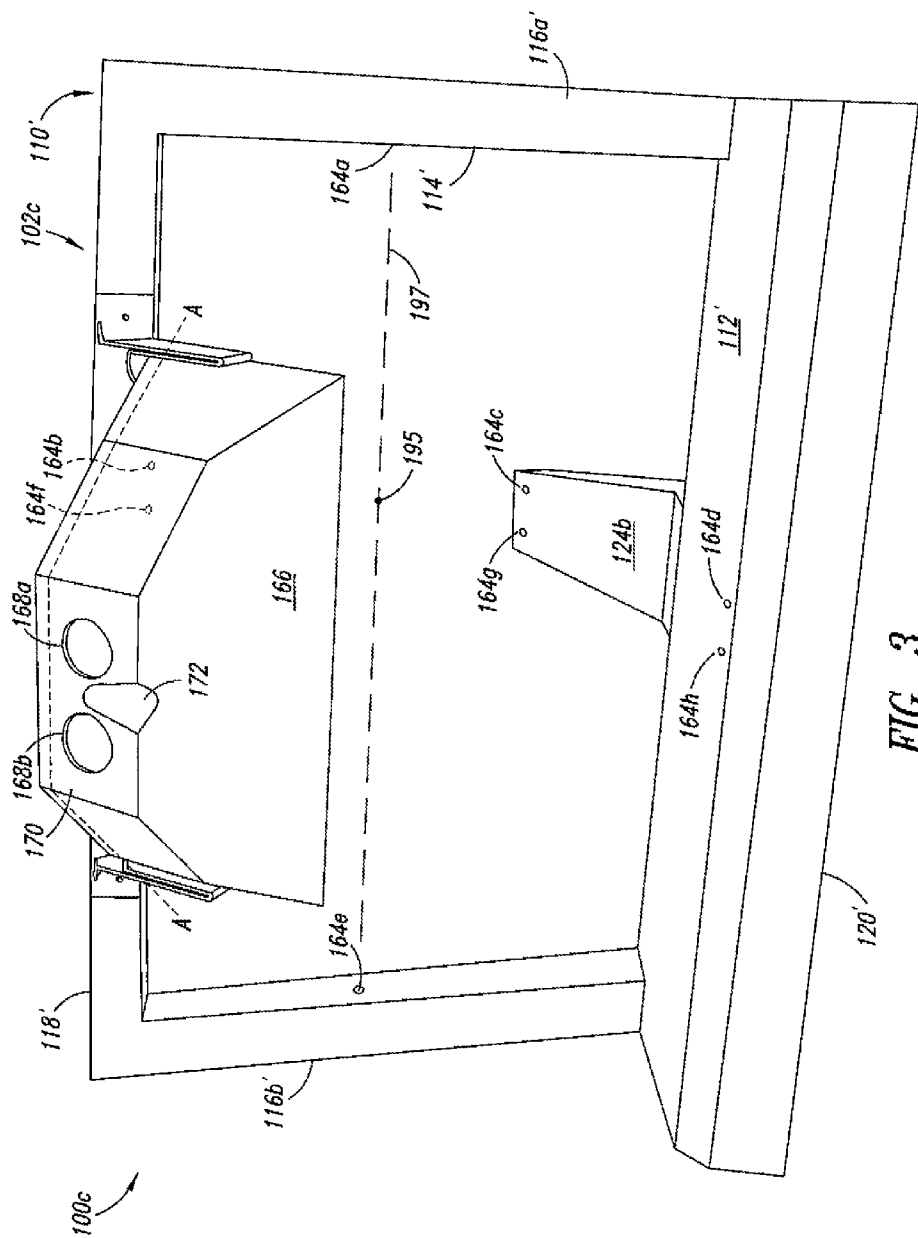


FIG. 3

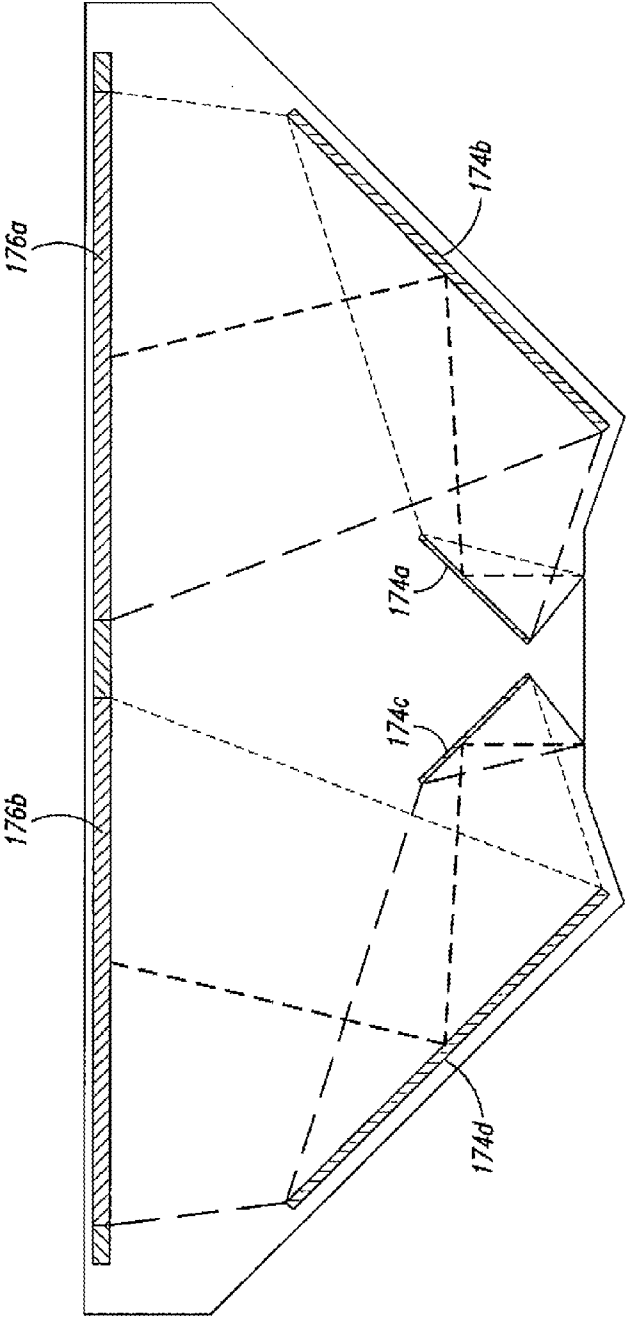


FIG. 4

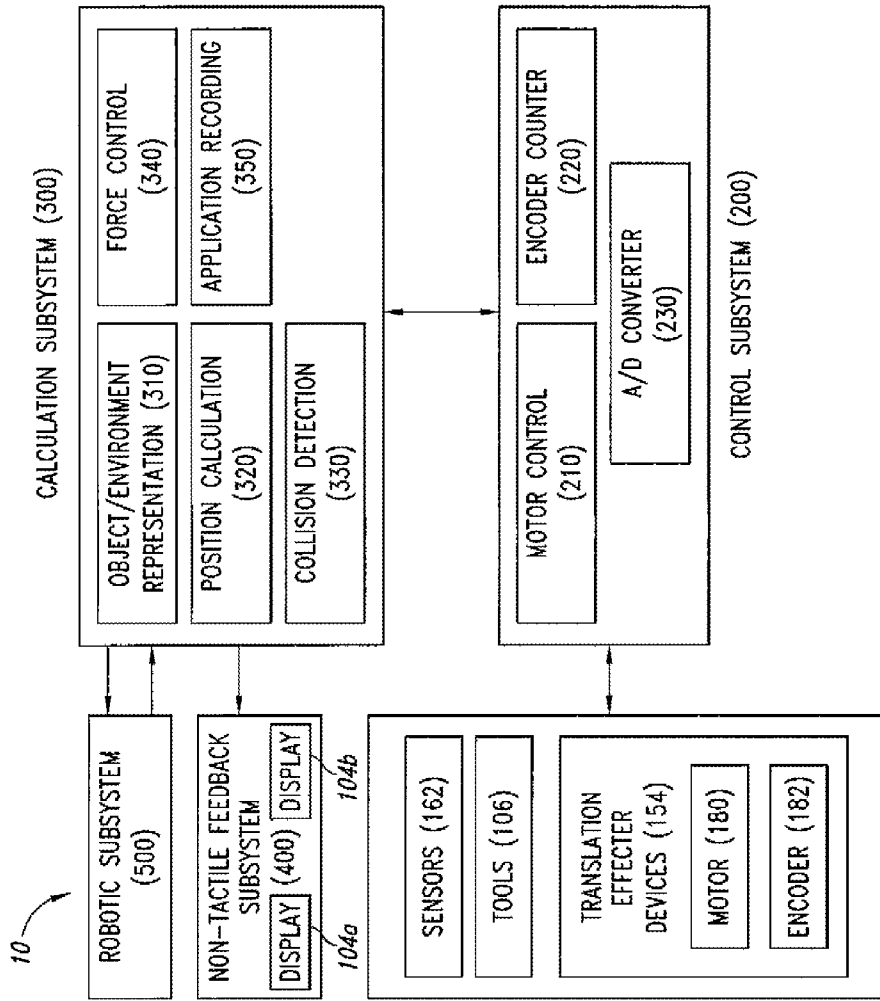


FIG. 5

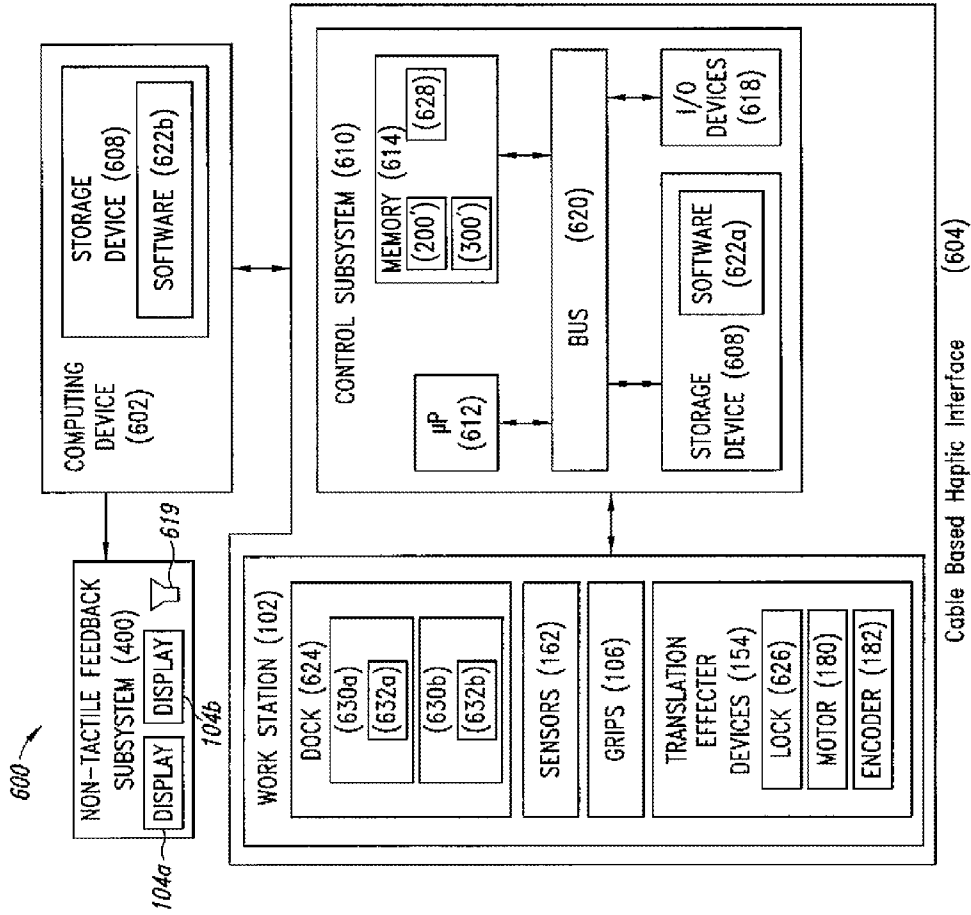


FIG. 6

Cable Based Haptic Interface (604)

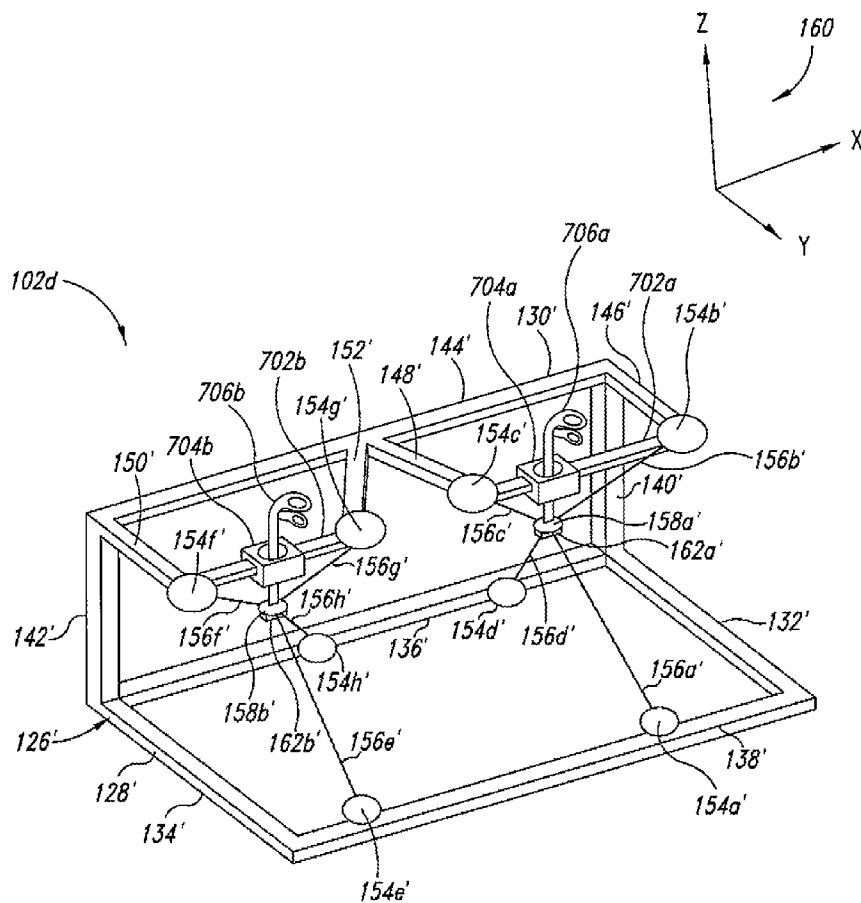


FIG. 7

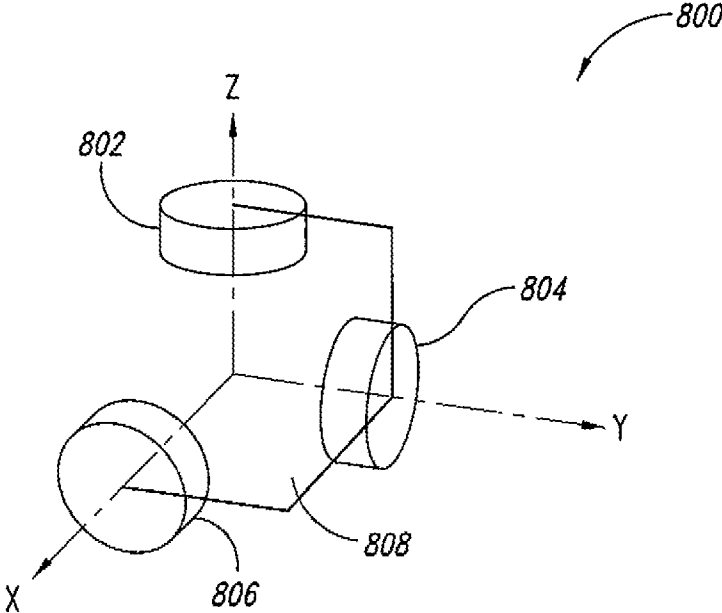


FIG. 8

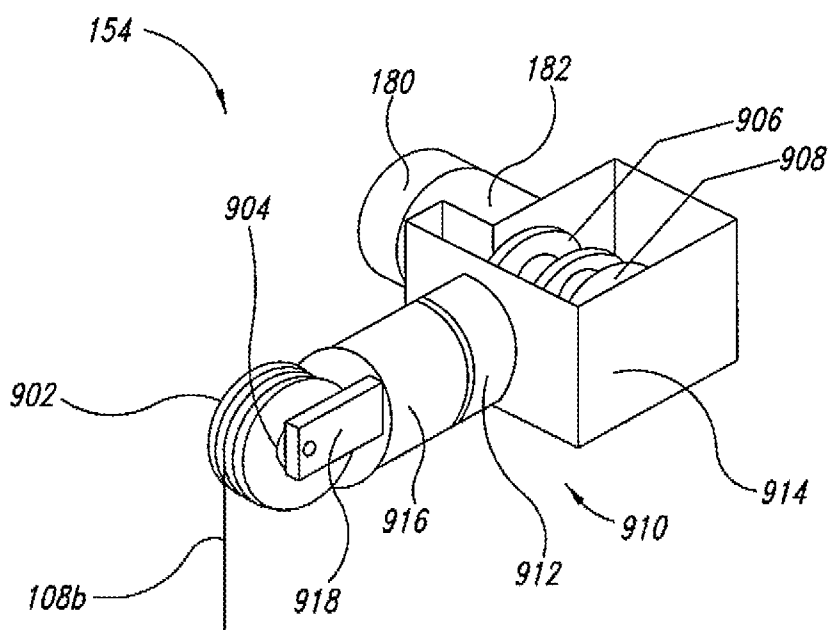


FIG. 9

METHODS, APPARATUS, AND ARTICLE FOR FORCE FEEDBACK BASED ON TENSION CONTROL AND TRACKING THROUGH CABLES

CROSS-REFERENCE TO RELATED APPLICATIONS

[0001] This continuation application claims priority from co-pending, commonly owned U.S. patent application Ser. No. 13/242,869, filed Sep. 23, 2011, which claims priority to U.S. patent application Ser. No. 11/947,398, filed Nov. 29, 2007, and issued as U.S. Pat. No. 8,054,289 on Nov. 8, 2011, and titled "Method, Apparatus, and Article for Force Feedback Based on Tension Control and Tracking Through Cables", which claims priority from U.S. Provisional Patent Application No. 60/868,318, filed Dec. 1, 2006, which applications are herein incorporated in their entirety by reference.

BACKGROUND

[0002] 1. Technical Field

[0003] The disclosure is generally related to haptic systems employing force feedback.

[0004] 2. Description of the Related Art

[0005] Touch, or haptic interaction is a fundamental way in which people perceive and effect change in the world around them. Our very understanding of the physics and geometry of the world begins by touching and physically interacting with objects in our environment. The human hand is a versatile organ that is able to press, grasp, squeeze or stroke objects; it can explore object properties such as surface texture, shape and softness; and it can manipulate tools such as a pen or wrench. Moreover, touch interaction differs fundamentally from all other sensory modalities in that it is intrinsically bilateral. We exchange energy between the physical world and ourselves as we push on it and it pushes back. Our ability to paint, sculpt and play musical instruments, among other things depends on physically performing the task and learning from the interactions.

[0006] Haptics is a recent enhancement to virtual environments allowing users to "touch" and feel the simulated objects with which they interact. Haptics is the science of touch. The word derives from the Greek haptikos meaning "being able to come into contact with." The study of haptics emerged from advances in virtual reality. Virtual reality is a form of human-computer interaction (as opposed to keyboard, mouse and monitor) providing a virtual environment that one can explore through direct interaction with our senses. To be able to interact with an environment, there must be feedback. For example, the user should be able to touch a virtual object and feel a response from it. This type of feedback is called haptic feedback.

[0007] In human-computer interaction, haptic feedback refers both to tactile and force feedback. Tactile, or touch feedback is the term applied to sensations felt by the skin. Tactile feedback allows users to feel things such as the texture of virtual surfaces, temperature and vibration. Force feedback reproduces directional forces that can result from solid boundaries, the weight of grasped virtual objects, mechanical compliance of an object and inertia.

[0008] Conventional haptic devices (or haptic interfaces) are typically mechanical devices that mediate communication between the user and the computer. Haptic devices allow users to touch, feel and manipulate three-dimensional objects

in virtual environments and tele-operated systems. Most common computer interface devices, such as basic mice and joysticks, are input-only devices, meaning that they track a user's physical manipulations but provide no manual feedback. As a result, information flows in only one direction, from the peripheral to the computer. Haptic devices are input-output devices, meaning that they track a user's physical manipulations (input) and provide realistic touch sensations coordinated with on-screen events (output). Examples of haptic devices include consumer peripheral devices equipped with special motors and sensors (e.g., force feedback joysticks and steering wheels) and more sophisticated devices designed for industrial, medical or scientific applications (e.g., PHANTOM™ device).

[0009] Haptic interfaces are relatively sophisticated devices. As a user manipulates the end effector, grip or handle on a haptic device, encoder output is transmitted to an interface controller. Here the information is processed to determine the position of the end effector. The position is then sent to the host computer running a supporting software application. If the supporting software determines that a reaction force is required, the host computer sends feedback forces to the device. Actuators (motors within the device) apply these forces based on mathematical models that simulate the desired sensations. For example, when simulating the feel of a rigid wall with a force feedback joystick, motors within the joystick apply forces that simulate the feel of encountering the wall. As the user moves the joystick to penetrate the wall, the motors apply a force that resists the penetration. The farther the user penetrates the wall, the harder the motors push back to force the joystick back to the wall surface. The end result is a sensation that feels like a physical encounter with an obstacle.

[0010] General-purpose commercial haptic interfaces used today can be classified as either ground based devices (force reflecting joysticks and linkage based devices) or body based devices (gloves, suits, exoskeletal devices). The most popular design on the market is a linkage based system, which consists of a robotic arm attached to a grip (usually a pen). A large variety of linkage based haptic devices have been patented (examples include U.S. Pat. Nos. 5,389,865; 5,576,727; 5,577,981; 5,587,937; 5,709,219; 5,828,813; 6,281,651; 6,413,229; and 6,417,638).

[0011] An alternative to a linkage based device is one that is tension based. Instead of applying force through links, cables are connected a point on a "grip" in order to exert a vector force on that grip. Encoders can be used to determine the lengths of the connecting cables, which in turn can be used to establish position of the cable connection point on the grip. Motors are used to create tension in the cables.

[0012] Predating Dr. Seahak Kim's work on the SPIDAR-G, Japanese Patent No. 2771010 and U.S. Pat. No. 5,305,429 were filed that describe a "3D input device" as titled in the patent. This system consists of a support means, display means and control means. The support means is a cubic frame. Attached to the frame are four encoders and magnetic switches capable of preventing string movement over a set of pulleys. The pulleys connect the tip of each encoder to strings that are wound through the pulleys. Each string continues out of the pulley to connect with a weight that generates passive tension in the string. The ON/OFF magnetic switches allow the strings to be clamped in place on command from the host computer. The strings connect to the user's fingertip, which are connected to the weights through the pulleys. The user

moves his or her fingertip to manipulate a virtual object in a virtual environment, which is displayed through a monitor. As the user moves his or her fingertip, the length of the four strings change, and a computer calculates a three-dimensional position based on the number of pulses from the encoder, which indicate the change of string length between the pulleys and the user's finger. If the three-dimensional position of the fingertip is found to collide with a virtual object as determined by a controlling host computer, then the ON/OFF magnetic switch is signaled to grasp and hold each string so that movement is resisted. Forces are not rendered in a specific direction, but resistance in all directions indicates that a user has contacted a virtual object. When the fingertip is forced outside the boundary of a virtual object, the magnetic switch is turned off to release the strings. The user is then able to move his or her finger freely.

[0013] A system that combines virtual reality with exercise is described in U.S. Pat. No. 5,577,981. This system uses sets of three cables with retracting pulleys and encoders to determine the position of points on a head mounted display. Using the lengths of the three cables, the position of the point in space is found. Tracking three points on the helmet (nine cables) allows head tracking of six degrees of freedom. Three cables attached to motor and encoders are also used to control the movement of a boom that rotates in one dimension through a vertical slit in a wall. The boom also has a servomotor at its end, about which the boom rotates. It is claimed that the force and direction of force applied by the boom can be controlled via the cables, servo motor and computer software, but no details are provided for how this is accomplished. U.S. Pat. No. 5,305,429 and U.S. Pat. No. 6,630,923 describe two cables based haptic interface devices.

[0014] Haptic interface devices can be used in a variety of fields for a variety of purposes. One field where haptic interface devices are currently employed is in simulating medical procedures for training medical personnel such as doctors in new techniques and/or for allowing medical personnel to practice old techniques. The practice of old or new techniques via a haptic interface device is especially important when the techniques are complicated and/or inherently risky to patients. Normally, conventional haptic interface devices can be large and for all practical purposes non-portable. Thus, hospitals and organizations that use a conventional haptic interface device normally dedicate a room for the conventional haptic interface device. This means that persons wanting or needing to use a conventional haptic interface device must go to the dedicated room in order to practice on the conventional haptic interface device, which can be very inconvenient to the persons wanting or needing to use the conventional haptic interface device. A problem with conventional haptic interface devices is that they may be underutilized due to the inconvenience of the user having to go to the dedicated room. Another problem is that hospitals and other organizations might not have the resources for housing the conventional haptic interface devices. Thus, there exists a need to overcome the aforementioned deficiencies.

BRIEF SUMMARY OF THE PRESENT DISCLOSURE

[0015] In one aspect, a haptic interface device comprises a first grip; a first set of a number of translation effector devices, the first set of translational effector devices including a first translational effector device, a second translational effector device, a third translational effector device, and a fourth trans-

lational effector device; a first set of a number of cables, each cable of the first set of cables having a first end and a second end, the first end of each first set of cables coupled to the first grip, and the second end of each first set of cables coupled to a respective one of the first set of translational effector devices; a second grip that moves independently of the first grip; a second set of a number of translation effector devices, the second set of translational effector devices including a first translational effector device, a second translational effector device, a third translational effector device, and a fourth translational effector device; a second set of a number of cables, each cable of the second set of cables having a first end and a second end, the first end of each second set of cables coupled to the second grip, and the second end of each second set of cables coupled to a respective one of the second set of translational effector devices; a translational effector device mounting means for mounting the first set of translational effector devices and the second set of translational effector devices in fixed positions, the translational effector device mounting means defining an opening having a transverse width, wherein the positions of first set of translational effector devices are transversely offset from the positions of the second set of translational effector devices.

[0016] In another aspect, a haptic interface device comprises a first grip configured to move within a volume of space, the first grip associated with a first movable robotic object; a second grip configured to move within the volume of space independent of the first grip, the second grip associated with a second movable robotic object; a first set of a number of translational effector devices, each translational effector device of the first set of translational effector devices having a motor and a spool, each motor configured to fractionally rotate a respective one of the spools, each one of the spools of the translational effector devices of the first set of translational effector devices having a cable coupled thereto, each one of the respective cables coupled to the first set of translational effector devices is coupled to the first grip, the first set of translational effector devices including four translational effector devices; a second set of a number of translational effector devices, each translational effector device of the second set of translational effector devices having a motor and a spool, each motor configured to fractionally rotate a respective one of the spools, each one of the spools of the translational effector devices of the second set of translational effector devices having a cable coupled thereto, each one of the respective cables coupled to the second set of translational effector devices is coupled to the second grip, the second set of translational effector devices including four translational effector devices; a frame having the first set of translational effector devices and the second set translational effector devices mounted thereon, the frame having a transverse width, wherein the first set of translational effector devices are transversely offset from the second set of translational effector devices; a first controller subsystem in direct communication with the motors of the first set of translational effector devices and in direct communication with the motors of the second set of translational effector devices, the first controller subsystem having a virtual reality (VR) collision detection module and a tracking module, the tracking module configured to receive signals from the first set of translational effector devices and configured to determine a position of the first grip based upon the signals from the first set of translational effector devices and configured to receive signals from the second set of translational effector devices and configured

to determine a position of the second grip based upon the signals from the second set of translational effector devices, the VR collision detection module having VR primitive shapes stored therein, the VR collision detection module configured to use the VR primitive shapes to simulate a VR environment having VR objects and determine collisions between the VR objects and at least one of the first robotic object or the second robotic object based upon the received signals.

[0017] In another aspect, a haptic interface device comprises a grip configured to move within a volume of space, the grip associated with a movable robotic object; a first cable having a first end and a second end, the first end coupled to the grip; a first tool translation effector device (translational effector device) having coupled thereto the second end of the first cable such that, as the grip is moved within the volume of space, the first cable is retracted or paid out accordingly by the first translational effector device; a grip dock configured to receive the first grip; and a cable lock configured to lock the first such that the locked cable cannot be further retracted or further paid out.

[0018] In another aspect, a haptic interface device comprises a grip configured to move within a volume of space, the grip associated with a movable robotic object; a set of a number of translational effector devices, each translational effector device of the set of translational effector devices having a motor and a spool, each motor configured to fractionally rotate a respective one of the spools, each one of the spools of the translational effector devices of the set of translational effector devices having a cable coupled thereto, each one of the respective cables coupled to the set of translational effector devices is coupled to the grip; a haptic controller subsystem in direct communication with the motors of the set of translational effector devices, the controller subsystem having a virtual reality (VR) collision detection module and a tracking module, the tracking module configured to receive signals from the set of translational effector devices and configured to determine a position of the grip based upon the signals from the set of translational effector devices, the VR collision detection module having VR primitive shapes stored therein, the VR collision detection module configured to use the VR primitive shapes to simulate a VR environment having VR objects and determine collisions between the VR objects and the robotic object or the second robotic object based upon the received signals, the haptic controller subsystem configured to provide a second haptic controller subsystem with information related to the VR environment.

BRIEF DESCRIPTION OF THE SEVERAL VIEWS OF THE DRAWINGS

[0019] In the drawings, identical reference numbers identify similar elements or acts. The sizes and relative positions of elements in the drawings are not necessarily drawn to scale. For example, the shapes of various elements and angles are not drawn to scale, and some of these elements are arbitrarily enlarged and positioned to improve drawing legibility. Further, the particular shapes of the elements as drawn, are not intended to convey any information regarding the actual shape of the particular elements, and have been solely selected for ease of recognition in the drawings.

[0020] FIG. 1 is an isometric view of a dual-handed haptic interface device according to one illustrated embodiment.

[0021] FIG. 2 is an isometric view of a dual-handed haptic interface device according to another illustrated embodiment.

[0022] FIG. 3 is an isometric view of a work station according to one illustrated embodiment.

[0023] FIG. 4 is a cross-sectional view of a stereoscope according to one illustrated embodiment.

[0024] FIG. 5 is a block diagram showing selected components of a dual-handed haptic interface device and how they relate to each other according to one illustrated embodiment.

[0025] FIG. 6 is a block diagram of a haptic interface system according to one illustrated embodiment.

[0026] FIG. 7 is an isometric view of a dual-handed haptic interface device according to another illustrated embodiment.

[0027] FIG. 8 is an isometric view of a sensor array according to an illustrated embodiment.

[0028] FIG. 9 is an isometric view of a translational effector device according to an illustrated embodiment.

DETAILED DESCRIPTION OF THE PRESENT DISCLOSURE

[0029] In the following description, certain specific details are set forth in order to provide a thorough understanding of various disclosed embodiments. However, one skilled in the relevant art will recognize that embodiments may be practiced without one or more of these specific details, or with other methods, components, materials, etc. In other instances, well-known structures associated with systems and methods for providing virtual reality using cable based haptic interface devices have not been shown or described in detail to avoid unnecessarily obscuring descriptions of the embodiments.

[0030] Unless the context requires otherwise, throughout the specification and claims which follow, the word “comprise” and variations thereof, such as, “comprises” and “comprising” are to be construed in an open, inclusive sense, that is as “including, but not limited to.”

[0031] Reference throughout this specification to “one embodiment” or “an embodiment” means that a particular feature, structure or characteristic described in connection with the embodiment is included in at least one embodiment. Thus, the appearances of the phrases “in one embodiment” or “in an embodiment” in various places throughout this specification are not necessarily all referring to the same embodiment. Furthermore, the particular features, structures, or characteristics may be combined in any suitable manner in one or more embodiments.

[0032] As used in this specification and the appended claims, the singular forms “a,” “an,” and “the” include plural referents unless the content clearly dictates otherwise. It should also be noted that the term “or” is generally employed in its sense including “and/or” unless the content clearly dictates otherwise.

[0033] The headings and Abstract of the Disclosure provided herein are for convenience only and do not interpret the scope or meaning of the embodiments.

[0034] FIG. 1 shows a dual-handed haptic interface device 100. The dual-handed haptic interface device 100 includes a workstation 102a and a display 104. The workstation 102a includes a frame 110 and a base 112. The base 112 defines a front side 120 and a rear side 122, which is proximal to the display 104 with respect to the front side 120. Extending from the front side 120 is a generally reclined L-shaped member 124a.

[0035] The frame 110 defines an opening 114 through which the user may view the display 104. The frame 110 includes two side arms, which are collectively referenced as 116 and individually referenced as 116a and 116b. The side

arms **116** extend generally upward from the front side **120** of the base **112** and may extend slightly rearward in the direction of the rear side **122**. A cross member **118** extends between the side arms **116**.

[0036] In the embodiment illustrated, the display **104** is disposed behind the workstation **102a** and is viewable by a user of the dual-handed haptic interface device **100**. Arrow **113** represents the line of sight of a user positioned proximal to the front side **120** of the frame **110**.

[0037] In some embodiments, the display **104** may be disposed beside, above, or below the workstation **102a**, such that the display **104** is viewable to a user. In some embodiments, the dual-handed haptic interface device **100** may not include the display **104**, and in yet other embodiments, the display **104** may be disposed or positioned such that the display **104** is partially or fully obscured to the user, or not viewable by a user.

[0038] The workstation **102a** includes a pair of movable grips referenced collectively as **106** and individually referenced as **106a** and **106b**. Movable grips include any tool, device, etc., that a user may manipulate.

[0039] Each one of the grips **106** is coupled to the frame **110** via respective sets of four cables (collectively referenced as **108** and individually referenced as **108a-108h**). Cables **108a-108d** are coupled to grip **106a** at an attachment end **109a**, and cables **108e-108h** are coupled to the grip **106b** at attachment end **109b**. In some embodiments, the grips **106** are removably coupled to the attachment ends so that different types of tools may be manipulated by a user.

[0040] The generally reclined L-shaped member **124a**, the side arms **116**, and the cross member **118** may be generally hollow and form a housing for a number of components such as, but not limited to, translation effector devices (not illustrated in FIG. 1). Embodiments of translation effector devices are described in U.S. Patent Publication No. US20050024331-A1, having Ser. No. 10/811,310, filed on Mar. 26, 2004, which is hereby incorporated by reference in its entirety.

[0041] In the embodiment illustrated in FIG. 1, cable **108a** extends from the attachment end **109a** toward the side arm **116a**; cable **108b** extends from the attachment end **109a** toward the cross member **118**; cable **108c** extends from the attachment end **109a** toward the rear side **122** of base **112**; and cable **108d** extends from the attachment end **109a** toward the generally reclined L-shaped member **124a**. Similarly, cable **108e** extends from the attachment end **109b** toward the side arm **116b**; cable **108f** extends from the attachment end **109b** toward the cross member **118**; cable **108g** extends from the attachment end **109b** toward the generally reclined L-shaped member **124a**; and cable **108h** extends from the attachment end **109b** toward the rear side **122** of base **112**.

[0042] FIG. 2 shows a second embodiment of a workstation **102b** according to an illustrated embodiment, with the display omitted for clarity of illustration. The workstation **102b** includes a skeletal frame **126** having a base **128** and support system **130**. The base **128** includes opposed sides **132**, **134** and opposed cross members **136**, **138** extending between the sides **132**, **134**.

[0043] The support system **130** includes a pair of opposed support members **140**, **142** extending generally upward from the base **128**. A cross member **144** extends between the support members **140**, **142**. Arms **146**, **148**, **150**, **152** extend outward, generally in the direction of cross member **138**, from the cross member **144**.

[0044] Translational effector devices **154b**, **154c**, **154f**, **154g** are coupled to the arms **146**, **148**, **150**, **152**, respectively. Translational effector devices **154h**, **154d** are coupled to the cross member **136**, and translational effector devices **154a**, **154e** are coupled to the cross member **138**.

[0045] The relative locations of the translational effector devices are given with reference to the Cartesian coordinate system **160**. The x-axis of the Cartesian coordinate system **160** is generally parallel to the cross member **144**, the y-axis of the Cartesian coordinate system **160** is generally parallel to the arm **132**, and the z-axis of the Cartesian coordinate system **160** is generally parallel to the support member **140**. The x-location of the translational effector devices **154a**, **154d** are in between the x-locations of the translational effector devices **154b**, **154c**. Similarly, the x-locations of the translational effector devices **154e**, **154h** are in between the x-locations of the translational effector devices **154f**, **154g**.

[0046] The y-locations of the translational effector devices **154b**, **154c** are in between the y-locations of the translational effector devices **154a**, **154d**. Similarly, the y-locations of the translational effector devices **154f**, **154g** are in between the y-locations of the translational effector devices **154e**, **154h**.

[0047] Cables **156a-156d** are coupled to a first attachment end **158a**, and cables **156e-156h** are coupled to a second attachment end **158b**. The cables are collectively referenced as **156** and individually referenced as **156a-156h**, and the attachment ends are collectively referenced as **158**.

[0048] Cable **156a**, **156b**, **156c**, **156d** extends from the attachment end **158a** to the translational effector device **154a**, **154b**, **154c**, **154d**, respectively. The translational effector devices **154a-154d** are each configured to pay out and retract cables **156a-156d**, respectively, in response to motion of the attachment end **158a**. Similarly, cable **156e**, **156f**, **156g**, **156h** extends from the attachment end **158b** to the translational effector device **154e**, **154f**, **154g**, **154h**, respectively. The translational effector devices **154e-154h** are each configured to pay out and retract cables **156e-156h**, respectively, in response to motion of the attachment end **158b**.

[0049] According to the embodiment illustrated in FIG. 2, each of the attachment ends **158** includes a sensor, which are collectively referenced as **162** and individually referenced as **162a**, **162b**. The sensors **162** may include one or more sensors, such as, but not limited to, gyroscopic sensors, acceleration sensors, infrared sensors, or electromagnetic sensors, tilt sensors which can relay signals to a control subsystem **200** (FIG. 5). The control subsystem **200** may use these signals to determine, among other things, the orientation, such as yaw, pitch, and roll, of the attachment ends **158**.

[0050] In some embodiments, an additional number of cables and a corresponding number of additional translational effector devices **154** can be used to provide one or more degrees of force feedback. Typically, for each additional degree of force feedback, an additional cable is connected to the grip and the corresponding translational effector device is coupled to the frame. Thus, to provide orientational force feedback such as pitch, roll, and yaw for one of the grips, then three more cables would be attached to the grip. In some embodiments, information related to additional parameters of a grip and/or a tool coupled to a grip may be determined via additional cables and corresponding translational effector devices. For example, a cable could be attached to a scissor-like handle of a tool to determine whether the scissor-like handle is open or closed.

[0051] FIG. 3 shows another embodiment of a dual-handed haptic interface device **100c** according to an illustrated embodiment, with the cables and grips omitted for clarity of illustration. In FIG. 3, the various labels having a reference numeral and a prime (') identify similar components and/or features as those of FIG. 1 that have the same reference numeral without a prime, and the various alphanumeric labels (e.g., labels having a reference numeral and a letter of the English alphabet) and a prime (') identify similar components and/or features as those of FIG. 1 that have the same alphanumeric labels without a prime.

[0052] Among other things, the dual-handed haptic interface device **100c** provides a user with stereoscopic viewing and includes a workstation **102c**. In some embodiments, the dual-handed haptic interface device **100c** may include the display **104** (not shown in FIG. 3).

[0053] In this embodiment, the front side **120'** does not have the generally reclined L-shaped member **124a** extending therefrom. Instead, two cable holes individually referenced as **164d** and **164h** are formed in the base **112'** proximal to the front side **120'**. Extending rearward from the rear side **122'** is a second generally reclined L-shaped member **124b**. The generally reclined L-shaped member **124b** has a second pair of cable holes, individually referenced as **164c** and **164g**. Another cable hole **164e** is formed in arm **116b'**. Similarly, a cable hole **164a** is formed in arm **116a'**. In addition, the cross member **118'** includes two cable holes **164b** and **164f**.

[0054] The cable holes **164a-164d** receive cables **108a-108d** (see FIG. 1) connected to the right side grip **106a** (see FIG. 1). Similarly, the cable holes **164e-164g** receive cables **108e-108h** (see FIG. 1) connected to the left side grip **106b** (see FIG. 1).

[0055] The cable holes **164a-164d** define the vertices of a first tetrahedron, and the cable holes **164e-164g** define the vertices of a second tetrahedron. In some embodiments, the first and second tetrahedrons are essentially back to back. In some embodiments, the first and second tetrahedrons are approximately symmetrically disposed about a midpoint **195** of a line **197** that extends between the hole **164a** and the hole **164e**. In this embodiment, it should be noted that translational effector devices are disposed within the frame **110** proximal to the cable holes **164a-164g**, and consequently, the translational effector devices also define the vertices of the two tetrahedrons.

[0056] The first tetrahedron defines the volume of space in which force feedback can be applied to the grip **106a**. When the grip **106a** is outside of the first tetrahedron, cable tension can be applied to pull the grip **106a** back into the first tetrahedron and/or to stop the grip **106a** from being moved further outside of the tetrahedron, but cable tension cannot be used to apply a force in any arbitrary direction. When the second grip **106b** is outside of the second tetrahedron, the same is true for the second grip **106b**. However, even when the grips **106** are outside of their respective tetrahedrons, the grips may still be tracked by the dual handed haptic interface device **100**.

[0057] A stereoscope **166** is coupled to the cross member **118'**. The stereoscope **166** includes a right side aperture **168a** and a left side aperture **168b**, both of which are formed in a front side **170**. The front side **170** may be contoured with a recess **172** that is shaped to receive a nose of a user. The stereoscope **166** is positioned such that it is angled downward and rearward with respect to a user.

[0058] FIG. 4 shows an embodiment of the stereoscope **166** according to the illustrated embodiment as viewed along line AA of FIG. 3.

[0059] The stereoscope **166** includes right side mirrors **174a, 174b** and left side mirrors **174c, 174d**. The right side mirrors **174a, 174b** are aligned to reflect light emitted from a right side display **176a** through the aperture **168a**. Similarly, the left side mirrors **174c, 174d** are aligned to reflect light emitted from a left side display **176b** through the aperture **168b**. In some embodiments, the stereoscope **166** may include other optical components such as prisms, lenses, and/or filters. For example, prisms could replace the mirrors **174a, 174c**.

[0060] In the embodiment illustrated in FIG. 4, the right and left side displays **176a, 176b** could be replaced by a single display on which split screen images are displayed. The displays **176a, 176b** may take the form of flat panel displays such as LCDs, plasma displays, or DPL displays. In some embodiments, the displays **176a** and **176b** are approximately 5 inches to 12 inches in diagonal size. This allows resolutions needed for virtual reality simulations and for appropriate refresh rates.

[0061] In some embodiments, the stereoscope **166** may be replaced by a stereoscopic viewer having optically transmissive elements such as color filters, or polarized filters, or shutters, etc. In such an embodiment, the stereoscopic viewer is positioned such that a portion of a display device (not shown in FIG. 3) may be viewable to a user of the stereoscopic viewer. The optically transmissive elements cooperate to provide a user with a stereoscopic view of the display device.

[0062] In some embodiments, stereoscopic vision may be provided by a user wearing special glasses or goggles and viewing a display device such as a monitor. For example, the user might wear "shutter-glasses" or polarized-glass or color-filter glasses. In yet other embodiments, the display device may be a stereoscopic projector or an auto stereoscope for providing stereoscopic images to a user without special glasses or goggles.

[0063] FIG. 5 shows an embodiment of a tension based force feedback system **10**. The tension based force feedback system **10** includes a workstation **102**, a control subsystem **200**, a calculation subsystem **300**, and may include an optional robotic system subsystem **500**. Among other things, the control subsystem **200** converts analog and pulse signals generated by sensors (e.g., encoders) of the workstation **102** into digital signals and relays force signals to the workstation **102**. Among other things, the calculation subsystem **300** controls force feedback, calculates the position of the grips **106**, and mathematically represents objects and/or environments that might interact with a virtual tool. A non-tactile feedback subsystem **400** provides a user of the tension based force feedback system **10** non-tactile stimuli (e.g., visual stimuli and/or audible and/or olfactory stimuli) about the virtual tool and virtual objects and/or environments, which are modeled in the calculation subsystem **300**. Among other things, the robotic subsystem **500**, which in those embodiments that are so configured, receives control instructions from, and provides feedback signals to, the calculation subsystem **300**.

[0064] As has been previously explained, according to some embodiments, each one of the grips **106** is removably coupled to attachment end **109** to which the cables **108** are attached. A separate grip or tool or device may then be coupled to the attachment end **109**. Accordingly, the sensors **162** may be configured to detect rotations of separate grips or

tools or devices attached to the attachment ends **158**, as one or both of the separate grips or tools or devices moves or rotates about one or more axes.

[0065] According to another embodiment, the attachment ends **109** may include a vibration element, whose frequency and magnitude of vibration are regulated by the control subsystem **200**. The vibration element may be used to create tactile effects. For example, vibration can be used to simulate different materials. For example, a dissipating vibration signal at a high frequency might be used when simulating contact with steel as compared to a dissipating vibration signal at a lower frequency, which could be used when simulating contact with wood. Suitable vibrational elements are generally known, such as those employed in paging devices and cellular phones, so will not be discussed in detail in the interest of brevity.

[0066] Each of the translational effector devices **154** includes a motor **180** and an encoder **182**. The motor **180** pays out and retracts one of the cables **108**. The encoder **182** converts rotations of a shaft of the motor **180** into electrical pulses that are provided to the control subsystem **200**. In some embodiments, the encoder **182** may advantageously take the form of a relative encoder avoiding the expense associated with absolute encoders.

[0067] Among other things, the control subsystem **200** receives the signals from the encoders **182** of each translation effector devices **154**, and sends control signals to the translational effector devices **154**. Typically, the control subsystem **200** includes three primary components: one or more motor controllers **210**, which control tension in each of the cables **108** via the motors **180** as directed by the calculation subsystem **300**; one or more encoder counters **220** that receive and count pulse signals from the encoders **182** and provides these counts to the calculation subsystem **300**; and one or more A/D converters **230** that convert analog signals transmitted from each of the translation effector devices **154** to digital signals that are relayed between the calculation subsystem **300** and the control subsystem **200**.

[0068] In one embodiment, the calculation subsystem **300** includes a local processor, memory storage and associated components on a printed circuit board for implementing local software control. In other embodiments, the calculation subsystem **300** may also include a remote computer, such as a conventional Pentium processor type or workstation with conventional memory and storage means. The remote computer may transfer data to the local processor through connections such as USB, serial, parallel, Ethernet, Firewire, SCSI, Bluetooth, serial connections, or any other manner or device for transferring data at a high rate. The calculation subsystem **300** processes information via software or firmware control. The calculation subsystem **300** may include five parts or submodules: an object/environment representation module **310**, a position calculation module **320**, a collision detection module **330**, a force control module **340**, and an application record module **350**.

[0069] According to one embodiment, some or all of the processing tasks, including those described with reference to the control subsystem **200** and the calculation subsystem **300**, may be performed by a conventional system or workstation.

[0070] Among other things, the object/environment representation module **310** manages and controls modeling information about virtual (or real) objects, the three-dimensional environment, and the grips **106**, and determines the proper interaction between the objects, the environment and the

grips **106**. The object/environment representation module **310** might also include information about the robotic subsystem **500**, information sent from the robotic subsystem **500**, and/or how movement of the grips **106** effects navigation of the robotic subsystem **500**. The visual representation of these objects is relayed from the object/environment representation module **310** to the non-tactile feedback subsystem **400**.

[0071] Among other things, the position calculation module **320** determines the position of the grips **106** by processing signals from the control subsystem **200** related to translation and rotational movement of one or both of the grips **106**.

[0072] Among other things, the collision detection module **330** determines whether a collision has occurred between one or more modeled objects and one or both of the grips **106**. This might also include an indication of existing environmental effects such as viscous resistance and inertia experienced as one or both of the grips **106** move through virtual fluid or against a virtual solid. When the system **10** is used to control a robot associated with the robotic subsystem **500**, collisions may be collected from the robot as it collides with real objects.

[0073] Among other things, the force control module **340** is used to calculate tension of each one of the cables **108** that is appropriate for rendering reaction forces that take place at one or both of the grips **106**. The summation of vector forces in the cables **108a-108d** will equal the reaction force at the grip **106a**, and similarly, the summation of vector forces in the cables **108e-108h** will equal the reaction force at the grip **106b**. Such forces might be the result of reaction forces collected by a robot as it interacts with real objects.

[0074] Among other things, the application record module **350** manages all other software interaction that takes place in an application that utilizes the system **10**.

[0075] The non-tactile feedback subsystem **400** displays virtual objects modeled through the calculation subsystem **300**. The non-tactile feedback subsystem **400** might also be used to convey visual information about real objects, such as in the case of using the system **10** to control the robotic subsystem **500** as it interacts with real objects. The non-tactile feedback subsystem **400** may include one or more display devices **104a** and **104b**, which may take the form of a conventional video monitor type and may be, for example, NTSC, PAL, VGA, or SVGA. The non-tactile feedback subsystem **400** may also include a head mounted display or a video projection system. The non-tactile feedback subsystem **400** may relay a 2-D representation or a stereoscopic representation for 3-D projection. The non-tactile feedback subsystem **400** might be used, for example, to collocate stereoscopic representations into the workspace of the system **10**. This could be accomplished by placing the display device **104** proximal to the rear side **122** such that the face of display device **104** is viewable through the opening **114**. Stereoscopic images may also be relayed through a head mounted display. The non-tactile feedback subsystem **400** may relay virtual environments where the entire environment can be classified as a rendered graphical image. The non-tactile feedback subsystem **400** may also transmit augmented environments where graphical rendering is overlaid onto video feeds or "see through" displays of real environments. The non-tactile feedback subsystem **400** could also transmit pure video of real environments, such as might be the case when the system **10** is used to control a robot operating in a real environment.

[0076] In some embodiments, the non-tactile feedback subsystem **400** may include at least two display devices **104a** and

104b. One of the display devices could be used to display a “right side” image, and another one of the display devices could be used to display a “left side” image. The “right side” image and the “left side” image may be combined into a three-dimensional (3-D) stereoscopic image. Alternatively, the non-tactile feedback subsystem may use split-screen technology to display the “right side” image and the “left side” on the same display device.

[0077] In one embodiment, the system **10** performs a variety of processes. A process to establish the initial length of each of the cables **108** is achieved through processing transmitted signals between the calculation subsystem **300** and each encoder counter device **182** and by utilizing a history of encoder pulse counts from each translation effector **154** as stored in the calculation subsystem **300**. The system **10** performs the process of relaying position and orientation (e.g., roll, pitch and yaw) information about the grips **106** to the calculation subsystem **300** through optical encoders and/or sensors such as gyroscopic sensors, acceleration sensors, tilt sensors, infrared or electromagnetic tracking mechanisms located in and/or around the grips **106**. The system **10** performs the process of establishing the position and orientation (e.g., roll, pitch and yaw) of the grips **106** in three-dimensional space at the calculation subsystem **300**. The system **10** performs the process of determining the position and orientation of the grips **106** with the calculation subsystem **300** from the signals sent by the control subsystem **200** and/or the grips **106** to the calculation subsystem **300**.

[0078] The system **10** further performs the process of establishing in the calculation subsystem **300** a force response that is appropriate at one or both of the grips **106** based on position and orientation of each of the grips **160** as each one of the grips **106** relate to virtual or real objects defined by the calculation subsystem **300**. The system **10** carries out the process by determining tension values in each one of the cables **108** such that the tension in the cables **108** will deliver the force response to one or both of the grips **106** as determined by the calculation subsystem **300**, and controlling tension in each one of the cables **108** by driving the motor **180** of each translation effector devices **154** based on the tension values determined by the calculation subsystem **300**. Finally, the system **10** performs the process of relaying visual and audible information via the non-tactile feedback subsystem **400** from the calculation subsystem **300** about the location and orientation of the grip **160** and virtual or real objects that the grip **106** may be interacting with.

[0079] FIG. **6** shows an embodiment of a haptic interface system **600** according to one illustrated embodiment. In FIG. **6**, the various labels that include a prime (') appended to a reference numeral (or a reference numeral and letter) identify similar components and/or features as those of prior figures that are labeled with the same reference numeral. The detailed description of such components are initially provided with respect to prior figures and for the sake of brevity the description of such components in the context of their subsequently prime-labeled counterparts in FIG. **6** are abbreviated or omitted.

[0080] The haptic interface system **600** includes a computing device **602** coupled to a cable based haptic interface **604** and coupled to a display device **400'**. The computing device **602** may be a personal computer, a work station, notebook computer, etc. Software carried in a computer readable medium such as a digital video disk (DVD), a compact disk (CD), etc. may be loaded into a storage device **608** such as a

hard drive of the computing device **602**. The software may include instruction sets for creating a virtual reality environment.

[0081] The cable based haptic interface **604** includes a control subsystem **610** and workstation **102'**. The control subsystem **610** includes a processor **612**, a memory **614**, a storage device **616**, and input/output devices **618**, all of which are coupled by at least one bus **620**. The I/O devices **618** may include input devices, for example but not limited to, a keyboard, mouse, microphone, touch sensitive display, etc. Furthermore, the I/O devices **618** may also include output devices, for example but not limited to, one or more display devices **104a**, **104b**, speakers **619**, etc. The I/O devices **618** may further include communication ports for communicating with the computing device **602**. I/O devices include IEEE 1394, USB, wireless (Bluetooth, etc.), serial binary data interconnection such as RS232, infrared data association (IrDA), DVD drives, CD drives, etc. In some embodiments, the I/O devices **618** include communication ports such that the translational effector devices **154** are in direct communication with the control subsystem **610**. In some embodiments, the number of I/O devices **618** is sufficient such that each one of the translational effector devices **154** is in direct and independent communication with the control subsystem **610**. In yet other embodiments, the number of I/O devices **618** is sufficient such that components of each one of the translational effector devices **154** is in direct and independent communication with the control subsystem **610**, e.g., for a given translational effector device **154**, the motor **180** and the encoder **182** may be in separate and direct communication with the control subsystem **610** via the I/O devices **618**. The I/O devices **618** may be configured to digitally control the translational effector devices **154** and/or the motors **180**.

[0082] In the embodiment illustrated, the storage device **616** includes haptic environmental software **622a**. The haptic environmental software **622a** may have been provided to the control subsystem **610** by the computing device **602** or may have been loaded into the storage device **616** via one of the I/O devices **618**. In some embodiments, the haptic environmental software **622a** or portions of the haptic environmental software **622a** may be loaded into the memory via the computing device **602**.

[0083] The haptic environmental software **622a** loaded in the storage device **616** is typically comprised of one or more modules that are a subset of a group of modules including haptic primitives (e.g., shapes such as, but not limited to, planes, cones, spheres, cubes, triangles, cylinders, boxes, polyhedrons, surfaces defined by non-uniform rational B-splines or NURBs, etc.), haptic effects (e.g., viscosity effects, centripetal and/or centrifugal forces, force fields such as electromagnetic/electrostatic attraction/repulsion, and gravitational force, etc.), and haptic textures (e.g., smooth, rough, elastic, sand paper, etc.). Typically, the haptic environmental software **622a** includes modules that relate to the VR objects included in a virtual environment. The haptic environmental software **622a** mimics motions of the grips **106** in the VR environment. In operation, the haptic environmental software **622a**, or portions of the haptic environmental software **622a**, may be stored or buffered in the memory **614**.

[0084] The calculation subsystem **300'** may implement one or more modules of the haptic environmental software **622a**. For example, the collision detection module (not illustrated in FIG. **6**) of the calculation subsystem **300'** may use the haptic primitives to determine whether a collision has occurred

between one or more modeled objects and one or both of the grips **106**. Similarly, the calculation subsystem **300'** might also determine environmental effects such as viscous resistance and inertia experienced as one or both of the grips **106** move through a virtual fluid or against a virtual solid.

[0085] In some embodiments, calculation subsystem **300'** may be configured to blend between different haptic regions or transition regions. For example, in the VR environment, there may exist a transition region between a first VR region and a second VR region. The first VR region may be best described or simulated using a first type of haptic primitive and/or a first type of haptic effect and/or a first type of haptic texture, and similarly, the second VR region may be best described or simulated using a second type of haptic primitive and/or a second type of haptic effect and/or a second type of haptic texture. In the transition region, the calculation subsystem **300'** may blend the first and second haptic primitives and/or blend the first and second haptic effects and/or blend the first and second haptic textures. In one embodiment, the blending may be implemented using interpolation.

[0086] The memory **614** includes, among other things, logic for the control subsystem **200'** and the calculation subsystem **300'**. The object/environment representation module **310** uses the haptic environmental software **622a** to, among other things, manage and control modeling information about virtual (or real) objects, the three-dimensional environment, the grips **106**, and determine the proper interaction between the objects, environment and the grips **106**.

[0087] The processor **612** is a hardware device for executing software, particularly that stored in memory **614**. The processor **612** can be any device for executing software instructions such as an Intel Xscale® processor. Non-limiting examples of a processor device include microprocessor, application-specific integrated circuit (ASIC), and field programmable gate array (FPGA). The processor **612** executes the software stored in the memory **614** and provides the computing device **602** with display related information. In particular, display related information may include information for the VR elements that mimic the motions of the grips **106** such as the VR positions and orientations of the VR elements, information related to the VR environment such as the deformation, if any, of an VR object, etc.

[0088] The storage device **608** of the computing device **602** also includes VR software **622b**. The VR software **622b** may be complementary to the haptic environmental software **622a** such that together the haptic environmental software **622a** and the VR software **622b** comprise an entire VR software packet. As previously described, the haptic environmental software **622a** may include modules that relate to the VR objects and relate tactile interactions, and the VR software **622b** may include modules that relate to aural output such as providing appropriate sounds for one or more of the VR elements, which relate to the one or more grips **106**, interacting with one or more VR objects, or modules that relate to visual characteristics of the VR environment such as VR lighting/shadowing, color, transparency, etc.

[0089] The computing device **602** receives the display related information from the control subsystem **610**. The computing device **602** uses the VR software **622b** and the display related information to generate an output that is provided to the display devices **104a**, **104b** of the non-tactile feedback subsystem **400**.

[0090] It should be noted that an advantage of system **600** is that the processes and calculations can be done in parallel. For

example, the control subsystem **610** can determine the positions of one or more of the grips **106** and provide the computing device **602** with the grip position information. The computing device **602** may use the grip position information to generate the display output at the same time that the control subsystem **610** is using the position information to calculate appropriate cable tensions. Another advantage is that outputs can be provided at different refresh rates. For example, the control subsystem **610** may provide feedback to a user via tension in the cables **108** and/or via a vibration element attached to one or more of the grips **106** at one refresh rate, and the computing device **602** may provide output to the display device **400** at a second refresh rate. For example, the control subsystem **610** may control the motors **180** at a refresh rate of approximately 1000 instructions per second, while the computing device may refresh the display device **104** at only 30 Hz. Another advantage of system **600** is that legacy systems, which may have very low refresh rates can be implemented on the system **600**. For example, the control subsystem **610** may provide on-board processing related to, among other things, grip location, grip tracking, grip orientation, and force feedback, which may require very fast refresh rates, and the computing device **602** may implement a legacy system having a very low refresh rate to provide the display device **400'** with content. Yet another advantage of system **600** is that control subsystem **610** can perform on-board processing, and some of the processing such as, but not limited to, blending of haptic regions and collision detection are performed much faster by the control subsystem **610** than by the computing device **602**. Faster collision detection prevents a user from moving a grip into and/or through a modeled solid object. If the collision detection module is being run at a low refresh rate, then a grip may be moved into and/or through a solid object before the collision detection module could detect the collision. Similarly, faster blending of haptic regions provides a user with a natural, e.g., less jerky, force feedback.

[0091] In some embodiments, the system **600** may provide jerky force feedback. The control subsystem **610** might include a snap-to module. The snap-to module can apply tensions to the cables that cause a user to feel that the grips are pulled into predetermined positions. Typically, the predetermined positions form a 3-dimensional grid. A user can use the grips **106** to manipulate modeled objects. The user might move, stretch, and rotate, etc. the modeled objects. Using force enabled "snap-to", a magnetic attraction can guide you to specific grid points or to points of interest on an object (i.e. vertices, centers, midpoints, ends, edges, etc). Force can be used to stabilize the user's movement and to provide control when scaling, shearing, aligning, translating, rotating, etc. The force feedback allows the user to sculpt objects with a consistency of clay or use pressure on a brush stroke to pain a thick line. In some embodiments, legacy software such as CAD software is loaded on the computing device **602**. The computing device **602** uses the legacy software to provide images to the display **104**, and the control subsystem **610** operates in parallel to regulate the haptics at a high update/refresh rate.

[0092] In this embodiment, the work station **102** includes a grip dock **624**. The grip dock **624** includes grip couplers collectively referenced as **630** and individually referenced as **630a** and **630b**. The grip couplers **630** are configured to receive the grips **106** and releasably hold the respective grip therein. Typically, the grip couplers **630** are pressure sensitive

such that the grip couplers **630** holds one of the grips **106** when that grip is placed/pressed into the grip coupler **630** and releases the grip **106** when a subsequent pressure/force is applied. The grip couplers **630** might also be magnetic. The grip dock **624** may be disposed on the base **112** of the frame **110** or on some other location of the work station **102**. In some embodiments, the work station **102** may include multiple grip docks. For example, the work station **102** may include a right side grip dock for the right side grip and a left side grip dock for the left side grip.

[0093] In the embodiment illustrated, each one of the grip couplers **630a** and **630b** include a grip detector **632a** and **632b**, respectively. The grip detector **632a** is configured to detect when one of the grips **106** is received by the grip coupler **630a** and when the respective grip is removed from the grip coupler **630a**. The grip detector **632b** is similarly configured to detect when one of the grips **106** is received by the grip coupler **630b** and when the respective grip is removed from the grip coupler **630b**. In some embodiments, the grip detectors **632a** and **632b** may take the form of a pressure switch.

[0094] The grip dock **624** sends a grip received signal to the control subsystem **610** in response to one of the grips **106** being received (docked) by the grip dock **624**. The grip dock **624** also sends a grip removed signal to the control subsystem **610** in response to one of the grips **106** being removed (undocked) from the grip dock **624**. In some embodiments, the grip received signal and the grip removed signal identify which one of the grips **106** was docked and undocked.

[0095] In this embodiment, each one of the translational effector devices **154** includes a lock **626**. The locks **626** are configured to lock the cable of each respective translational effector devices in stationary position in response to a lock signal from the control subsystem **610** and to release the cable in response to an unlock signal from the control subsystem **610**.

[0096] In some embodiments, when the control subsystem **610** receives a grip received signal from the grip dock **624**, the control subsystem **610** determines which grip was docked. The control subsystem **610** could determine which grip was docked based upon tracking information, i.e., the current positions of the grips. Alternatively, the control subsystem may determine which grip dock sent the grip received signal. Upon determining which grip was “docked” and/or which grip dock sent the grip received signal, the control subsystem **610** sends a lock signal to the locks **626** of the translational effector devices **154** that are coupled to the “docked” grip. In response thereto, the locks **626** lock the cables in stationary position. And, when the control subsystem **610** receives a grip removed signal from the grip dock **624**, the control subsystem **610** determines which grip was undocked. The control subsystem **610** could determine which grip was undocked based upon which grip was previously docked. Alternatively, the control subsystem **610** may determine which grip dock sent the grip removed signal. Upon determining which grip was undocked and/or which grip dock sent the grip removed signal, the control subsystem **610** sends an unlock signal to the locks **626** of the translational effector devices **154** that are coupled to the undocked grip. In response thereto, the locks **626** unlock the cables.

[0097] In some embodiments, the locks **626** may be actuated to lock and unlock the cables with the grips being in any position in response to lock and unlock signals from the control subsystem **610**. A user might decide to lock the cables

prior to moving the work station **102** and unlock the cables after moving the work station **102**. A user might cause the control subsystem **610** to send lock/unlock signals to the locks **626** by using a lock/unlock switch (not shown) or by providing a user command via the I/O devices **618**.

[0098] During operation, the cables are paid out and retracted by the translational effector devices **154**, and after extended periods of use, the calculated lengths of the cables, as determined by the control subsystem **610**, may be different than the actual lengths. Consequently, in some embodiments, the control subsystem **610** includes a recalibration module **628** stored in the memory **614**. The recalibration module **628** is configured to calibrate calculated cable lengths. The recalibration module **628** may be engaged whenever a grip is positioned at a reference point. The recalibration module **628** knows the actual cable lengths from each of the translational effector devices **154** to the reference point and resets the calculated cables lengths accordingly. In one embodiment, the recalibration module **628** may be automatically initiated when a grip is received by the dock **624**.

[0099] In one embodiment, the memory **614** includes an operation log **628**. Among other things, the operation log **628** provides a record of the forces rendered to the grips **106** and a record of the trajectories of the grips **106**. The operation log **628** may be accessible to authorized personnel for, among other things, diagnostic purposes.

[0100] FIG. 7 shows a fourth embodiment of a workstation **102d** according to an illustrated embodiment, with the display omitted for clarity of illustration. In FIG. 7, the various labels having a reference numeral and a prime (') identify similar components and/or features as those of FIG. 2 that have the same reference numeral without a prime and the various alphanumeric labels (e.g., labels having a reference numeral and a letter of the English alphabet) and a prime (') identify similar components and/or features as those of FIG. 7 that have the same alphanumeric labels without a prime. The detailed description of such components and/or features are initially provided with respect to the embodiment of FIG. 2 and for the sake of brevity the description of such components and/or features in the context of their subsequently prime-labeled counterparts in FIG. 7 are abbreviated or omitted.

[0101] The workstation **102d** includes a first connecting arm **702a** that extends between support members **146'** and **148'** and a second connecting arm **702b** that extends between support members **150'** and **152'**. A first tool coupler **704a** is attached to the first connecting arm **702a**, and a first tool shaft **706a** passes through the first tool coupler **704a**. The first tool shaft **706a** is coupled to the first attachment end **158a'**, which has cables **156a'-156a'** coupled thereto.

[0102] A second tool coupler **704b** is attached to the second connecting arm **702b**, and a second tool shaft **706b** passes through the second tool coupler **704b**. The second tool shaft **706b** is coupled to the second attachment end **158b'**, which has cables **156b'-156b'** coupled thereto.

[0103] In some embodiments, the first and second tool couplers **704a** and **704b** are configured to pivotally couple with the first tool shaft **706a** and second tool shaft **706b**, respectively. The first and second tool couplers **704a** and **704b** may allow three or more degrees of freedom for the first and second tool shafts **706a** and **706b**, respectively. For example the first tool coupler **704a** may provide for two degrees of rotational freedom about the first tool coupler **704a** and insertion through the first tool coupler **704a**.

[0104] The motion of the attachment ends **158a'** and **158b'** is controlled through tension in cables **156a'-156d'** and cables **156e'-156h'**, respectively. The motion of the attachment ends **158a'** and **158b'** is such that a user will feel an insertion force (along with pitch and yaw) via the tool shafts **706a** and **706b**, respectively. Insertion forces are along the longitudinal length of the tool shafts **706a** and **706b** as confined by the tool couplers **704a** and **704b**. Pitch and yaw are felt on the tool shaft **706a** and the tool shaft **706b** with the respective pivot points at the tool couplers **704a** and **704b**. Such a configuration is ideal to apply three degrees of freedom force feedback to minimally invasive instruments used when simulating a surgical procedure.

[0105] More degrees of force feedback, such as rotation around the tool shaft **706a** (or **706b**) and grip forces at a handle of the tool shaft **706a** (or **706b**), can be added through additional motors and/or cables. For example, a motor in the tool shaft **706a**, or attached to the tool coupler **704a**, allows twisting force feedback, and a motor in a handle of the tool shaft **706a** adds a squeezing grip force.

[0106] In some embodiments, the workstation **102d** may include more than two tool couplers. The workstation **102d** may be configured to allow multiple users to use the workstation **102d** simultaneously. Such a configuration may be used to allow a team of users such as surgeons to practice complex procedures in close proximity.

[0107] FIG. 8 shows a sensor array **800** according to one illustrated embodiment. The sensor array **800** includes three optical rotary encoders **802**, **804**, and **806** coupled to a gimbal-like support system **808**. The three optical rotary encoders **802**, **804**, and **806** are arranged along three mutually orthogonal axes. The gimbal-like support system **808** is coupled to one of the cables **108** proximal to a grip **106**. The three optical rotary encoders **802**, **804**, and **806** provide the calculation subsystem **300** with information that is used to determine the orientation (roll, pitch, and yaw) of the grip **106**.

[0108] FIG. 9 shows a translational effector device **154** according to one illustrated embodiment. The illustrated translational effector device **154** is disposed within the cross member **118** of the frame **110**. The illustrated translational effector device **154** is generally representative of the other translation effector devices included in the workstation **102** according to the one illustrated embodiment.

[0109] The translation effector device **154** includes a pulley **902**, a first bearing **904**, motor **180**, encoder **182**, a spool **906**, cable **108b**, and a lockable motor brake **908**. The lockable motor brake **908** may include the lock **626**.

[0110] The translation effector device **154** is oriented so that the spool **906** generally guides the cable **108b** toward the grip **106a** with the objective of minimizing friction in the cable run (i.e., path) to the grip **106a**.

[0111] The translation effector device **154** also includes a mounting system **910** that guides the cable **108b** from the spool **906** to the pulley **902**, while providing stability for the spool **906** and the pulley **902**, such that spool **906** and the pulley **902** remain in fixed relative position when tension is applied to the cable **108b**. The mounting system **910** also provides a structure to couple the translation effector device **154** to the frame **110**. The mounting system **910** also positions the pulley **902** away from both the frame **110** and the spool **906** in a manner that enables ideal use of tool workspace. The mounting system **910** may vary in size or geometry depending on workspace requirements.

[0112] The mounting system **910** includes a link **912** that is fixed to a bracket **914**. A rotary fulcrum **916** is attached to link **912** through a secondary bearing. The rotary fulcrum **916** can rotate about an axis that is perpendicular to the adjacent face of link **912**.

[0113] The pulley **902** is mounted to the rotary fulcrum **916** through bracket **918**. The pulley **902** rotates around bearing **904**, which lies between bracket **918** and the pulley **902**. In addition to its attachment to link **912**, bracket **914** is attached to the motor **180**, the lockable brake **908**, and also to the cross member **118** of the frame **110**.

[0114] The motor **180** is typically a DC motor that displays minimal back drive friction and that is digitally controlled by the control subsystem **200** and/or **610**. The motor **180** includes a shaft that is drivingly coupled to the spool **906**, which is in turn coupled to a cable **108b**. When the motor **180** turns the spool **906**, the cable **108b** wraps or unwraps around the spool **906**. Tension occurs in the cable **108b** since the cables **108a-108d** pull at the attachment end **109a** in opposing directions. The amount of tension in the cable **108b** is based on the torque applied by the motor **180** to the spool **906** as governed by the control subsystem **200** and/or **610**. In order to reduce backlash, a gear is not used, however some embodiments may include a gear where suitable.

[0115] The encoder **182** is coupled to the motor **180** and generates electrical pulses in response to rotation of the motor shaft. The electrical pulses are sent to the control subsystem **200** and/or **610**. Typically, an optical encoder is used with a resolution of 1024 pulses per rotation of the motor shaft. However, a variety of optical encoders can be used that have a wide range of resolutions. An encoder is therefore chosen based on application requirements and price constraints. Determining translational movement of the grip **106a** can be calculated from the length of each of the cables **108a-108d**, which is determined from encoder pulse signals. There is a mathematical relationship between cable length change, diameter of the spool **906**, and the pulses per rotation. The spool **906** can be made of a variety of materials, such as aluminum, steel, rigid plastic or any other stiff material.

[0116] Although not shown in any figure, a set of cables may be applied to multiple points on a grip so that different vector forces can be rendered at each point. A single calculation device can be used to control all the cable sets, or different calculation devices, for example on separate circuit boards, may be used. The effect of applying separate force vectors to different points on a single grip yields the effect of rotational forces as felt by the user, or may serve to control the movement of a jointed grip. Multiple sets of cables can also be used to apply force vectors to multiple grips that exist in the same workspace.

[0117] Although specific embodiments of and examples for the haptic system and method are described herein for illustrative purposes, various equivalent modifications can be made without departing from the spirit and scope of the present disclosure, as will be recognized by those skilled in the relevant art. The teachings provided herein of the present disclosure can be applied to other haptic systems, not necessarily the exemplary haptic system **10** generally described above.

[0118] The various embodiments described above can be combined to provide further embodiments. All of the above U.S. patents, U.S. patent application publications, U.S. patent applications, foreign patents, foreign patent applications and non-patent publications referred to in this specification and/or

listed in the Application Data Sheet, including but not limited to U.S. Pat. No. 5,305,429; Seahak Kim, Masahiro Ishii, Yasuharu Koike, Makoto Sato, "Development of Tension Based Haptic Interface with 7 DOF:SPIDAR-G," ICAT2000, 25-27, Oct., 2000, National Taiwan University, Taiwan; Seahak Kim, Masahiro Ishii, Yasuharu Koike, Makoto Sato, "Design of a Tension Based Haptic Interface with 6 DOF," 4th World Multiconference on Systemics, Cybernetics and Informatics (SCI2000) and the 6th International Conference on Information Systems Analysis and Synthesis (ISA52000), Orlando, USA, in Jul. 23-26, 2000; Seahak Kim, Masahiro Ishii, Yasuharu Koike, Makoto Sato, "Development of SPIDAR-G and Possibility of its Application to Virtual Reality," VRST2000, 22-25, Oct., 2000, Seoul, Korea; Seahak Kim, Masahiro Ishii, Yasuharu Koike, Makoto Sato, "Design of tension based haptic interface: SPIDAR-G," IMECE2000 (joint with ASME2000), 5-10, Nov., 2000, Orlando, USA; Seahak Kim, Masahiro Ishii, Yasuharu Koike, Makoto Sato, "Cutting edge Haptic interface device: SPIDAR-G," Proceedings of the 32nd ISR (International Symposium on Robotics), 19-21, Apr., 2001, Seoul, Korea; Seahak Kim, Shoichi Hasegawa, Yasuharu Koike, Makoto Sato, "Tension Based 7 DOFs Force Feedback Device: SPIDAR-G" by the IEEE Computer Society Press in the proceedings of the IEEE Virtual Reality Conference 2002, 24-28 Mar. 2002 in Orlando, Fla.; Seahak Kim, Shoichi Hasegawa, Yasuharu Koike, Makoto Sato, "Tension based 7 DOF Force Feedback Device," Trans. On ICASE, Vol. 4, No. 1, pp. 8-16, 2002; Seahak Kim, Jeffrey J. Berkley, and Makoto Sato, "A Novel Seven Degree of Freedom Haptic Device for Engineering Design," Journal of virtual reality, Springer UK (accepted), are incorporated herein by reference, in their entirety. Aspects of the present disclosure can be modified, if necessary, to employ systems, circuits and concepts of the various patents, applications and publications to provide yet further embodiments of the present disclosure.

[0119] These and other changes can be made to the embodiments in light of the above-detailed description. In general, in the following claims, the terms used should not be construed to limit the claims to the specific embodiments disclosed in the specification and the claims, but should be construed to include all possible embodiments along with the full scope of equivalents to which such claims are entitled. Accordingly, the claims are not limited by the disclosure.

1. (canceled)
2. A haptic based system for controlling a robot, comprising:
 - a haptic user interface including a right side set of at least four cable segments, a left side set of at least four cable segments, a right side grip and a left side grip, a structure having a front user side and an opposed rear side separated from the front user side by a longitudinal distance, the structure defining a transverse width extending generally between opposed right and left sides of the structure, wherein the right and left sides of the structure are generally vertically aligned, wherein at least four points of the structure define a set of right side cable feeds and at least four other points of the structure define a set of left side cable feeds, each point of the set of right side cable feeds configured to have a respective cable segment of the right side set of at least four cable segments extending therefrom to the right side grip, each point of the set of left side cable feeds configured to have a respective cable segment of the left side set of at least

- four cable segments extending therefrom to the left side grip, wherein a first cable feed of the set of right side cable feeds is disposed at the right side of the structure, and wherein a first cable feed of the set of left side cable feeds is disposed at the left side of the structure, wherein the other cable feeds are disposed proximal to a plane that is located at an approximate midpoint of the transverse width; and
 - a controller that receives signals that are indicative of movement of at least one of the right side and the left side grips, the controller configured to track motion of the right side and the left side grips based at least in part on the received signals and configured to determine robot control signals for controlling movement of a robot such that the movement of the robot corresponds to the tracked motion of the right side grip and the left side grip.
3. The haptic based system of claim 1, further comprising:
 - a stereoscopic display system that displays to a user a stereoscopic image of at least a portion of the robot moving in accordance with the tracked motion of the right side grip and the left side grip.
 4. The haptic based system of claim 1, further comprising:
 - a first plurality of translational effector devices coupled to the right side set of at least four cable segments that are configured to play out and retract each of the right side set of at least four cable segments; and
 - a second plurality of translational effector devices coupled to the left side set of at least four cable segments that are configured to play out and retract each of the left side set of at least four cable segments.
 5. The haptic based system of claim 3, wherein the set of right side cable feeds define vertices of a right side tetrahedron, wherein the set of left side cable feeds define vertices of a left side tetrahedron, wherein the first plurality of translational effector devices are further configured to apply active tension to the right side set of at least four cable segments, which results in a net force applied to the right side grip, such that a direction of the net force applied to the right side grip is in any predetermined first direction when the right side grip is located within the right side tetrahedron, and wherein the second plurality of translational effector devices are further configured to apply active tension to the left side set of at least four cable segments, which results in a net force applied to the left side grip, such that a direction of the net force applied to the left side grip is in any predetermined second direction when the left side grip is located within the left side tetrahedron.
 6. The haptic based system of claim 1, wherein the controller is a first controller that is further configured to determine a current position of the right side and the left side grip, and further comprising:
 - a second controller, in communication with the first controller, configured to determine content for display by a display device based at least in part on the current positions of the right side and the left side grips.
 7. The haptic based system of claim 5, wherein the first controller is further configured to calculate amounts of active tension applied to each of the right side set of at least four cable segments and to each of the left side set of at least four cable segments, which results in a first net force applied to the right side grip and a second net force applied to the left side grip, based at least in part the current positions of the right side and the left side grips, and wherein the first controller and the second controller act in parallel.

8. The haptic based system of claim 6, further comprising:
 a first plurality of translational effector devices coupled to the right side set of at least four cable segments that are configured to play out and retract, responsive to signals from the first controller, each of the right side set of at least four cable segments such that tension in each of the right side set of at least four cable segments results in the first net force being applied to the right side grip; and
 a second plurality of translational effector devices coupled to the left side set of at least four cable segments that are configured to play out and retract, responsive to signals from the first controller, each of the left side set of at least four cable segments such that tension in each of the left side set of at least four cable segments results in the second net force being applied to the left side grip.

9. The haptic based system of claim 7, wherein the first controller provides refresh signals to the first and the second plurality of translational effector devices at a first refresh rate, and wherein the second controller provides refresh signals to the display device at a second refresh rate, which is slower than the first refresh rate.

10. A haptic based system for controlling a robot, comprising:

a haptic user interface including a right side set of at least two cable segments, a left side set of at least two cable segments, a right side grip and a left side grip, a structure having a front user side and an opposed rear side separated from the front user side by a longitudinal distance, the structure defining a transverse width extending generally between opposed right and left sides of the structure, wherein the right and left sides of the structure are generally vertically aligned, wherein at least two points of the structure define a set of right side cable feeds and at least two other points of the structure define a set of left side cable feeds, each point of the set of right side cable feeds configured to have a respective cable segment of the right side set of at least two cable segments extending therefrom to the right side grip, each point of the set of left side cable feeds configured to have a respective cable segment of the left side set of at least two cable segments extending therefrom to the left side grip, wherein a first cable feed of the set of right side cable feeds is disposed at the right side of the structure, wherein a second cable feed of the set of right side cable feeds is located proximal to a plane that is located at an approximate midpoint of the transverse width, wherein a first cable feed of the set of left side cable feeds is disposed at the left side of the structure, wherein a second cable feed of the set of left side cable feeds is located proximal to proximal to the plane; and

a first controller that receives signals that are indicative of movement of at least one of the right side and the left side grips, the first controller configured determine current positions of the right side and the left side grips based at least in part on the received signals and configured to determine robot control signals for controlling movement of a robot such the movement of the robot corresponds to the current positions of the right side grip and the left side grip; and

a second controller that receives current grip position information from the first controller and that is configured to determine content for display on a display device based at least in part on the received current grip position

information, and wherein the first controller and the second controller act in parallel.

11. The haptic based system of claim 9, wherein the first controller provides the robot control signals at a first refresh rate, and the second controller provides refresh signals to a display device at a second refresh rate, which is slower than the first refresh rate

12. The haptic based system of claim 10, wherein the first controller includes a memory that stores virtual reality primitives and determines the robot control signals based at least in part on the determined current positions of the right side and the left side grips and the virtual reality primitives, and wherein the second controller includes a memory that virtual reality data and determines a virtual reality environment based at least in part on the current grip position information and the virtual reality data, wherein the content for display includes at least a portion of the determined virtual reality environment.

13. The haptic based system of claim 9, further comprising:
 a stereoscopic display system that displays to a user a stereoscopic image of at least a portion of the robot moving in accordance with movement of the right side grip and the left side grip.

14. The haptic based system of claim 9, wherein the first cable feed of the set of right side cable feeds is vertically disposed proximal to a midpoint the right side of the structure, and wherein the first cable feed of the set of left side cable feeds is vertically disposed proximal to a midpoint the left side of the structure.

15. A method of controlling a robot, comprising:

providing a dual handed cable-based haptic user interface having generally back-to-back right and left side work space volumes disposed about a plane located at an approximate transverse width of the dual handed cable-based haptic user interface, wherein the dual handed cable-based haptic user interface includes a front user side and an opposed rear side separated from the front user side by a longitudinal distance and defines a transverse width extending generally between opposed right and left sides of the dual handed cable-based haptic user interface, wherein at least four points of the dual handed cable-based haptic user interface define vertices of the right side workspace volume and at least four other points of the dual handed cable-based haptic user interface define vertices of the left side workspace volume, wherein a vertex that defines the right side workspace volume is located at the right side of the dual handed cable-based haptic user interface, and wherein a vertex that defines the left side workspace volume is located at the left side of the dual handed cable-based haptic user interface;

tracking motion of a right side grip and a left side grip, inside of the right side workspace volume and the left side workspace volume, respectively, being manipulated by a user, wherein the right side grip is coupled to a first set of at least four cable segments that extend between the right side grip and the at least four points that define the vertices of the right side workspace volume, and wherein the left side grip is coupled to second set of at least four cable segments that extend between the left side grip and the at least four points that define the vertices of the left side workspace volume;

determining a current position of the right side grip and the left side grip based at least in part on the tracked motion thereof; and

providing robot control signals that control movement of a robot such the movement of the robot corresponds to the tracked motion of the right side grip and the left side grip.

16. The method of claim **14**, wherein the robot is a virtual robot.

17. The method of claim **14**, wherein the robot is a real non-virtual robot.

18. The method of claim **14**, further comprising:
providing a display device with images of at least a portion of the robot moving in accordance with the tracked motion of the right side grip and the left side grip.

19. The method of claim **14**, further comprising:
providing force feedback to the user through active tension applied to the first and the second sets of at least four cable segments.

20. The method of claim **14**, further comprising:

providing a display device with images of at least a portion of the robot moving in accordance with the tracked motion of the right side grip and the left side grip; and

providing force feedback to the user through active tension applied to the first and the second sets of at least four cable segments.

21. The method of claim **19**, further comprising:

providing, at a first refresh rate, refresh signals to control the active tension applied to the first and the second sets of at least four cable segments; and

providing, at a second refresh rate, refresh signals to the display device, wherein the first refresh rate is in the range of approximately two hundred to seven hundred (200-700) times faster than the second refresh rate.

* * * * *