

**Title:**

Precise Task Control in Teleoperation.

Abstract:

Teleoperation technology could help and substitute human to perform tasks conveniently in the long-distance or dangerous environment. One key point of teleoperation is how to make the operator get the force information which is generated when the slave robot interfaces with the environment, and make the slave robot follow the movement of the master hand controller in an accurate and timely manner. The teleoperation system becomes more and more popular and has been applied in nuclear power, space and telemedicine and also other areas. However, precise task control, as for a teleoperation control for the eye, heart surgery, is now still a hot and hard topic in the teleoperation area, because it is usually not easy to establish the precise unknown working environment model in the slave robot side, and the operator always could not feel the exact force he imposed to the master hand controller and the contact force generated by the slave robot during the interface with the environment. The ultimate goal of precise task control in teleoperation is help the operator know clearly and precisely the location of the end of slave robot and also master how much force the robot has imposed to the precise task object, and make the operator could succeed to fulfil the precise task smoothly and safely.

Scope and Topics:

Potential topics include but are not limited to:

- ✧ Human-Robot Interface
- ✧ Human-Computer Interface
- ✧ High Precision Torque Sensors
- ✧ Information Fusion in Bilateral Control
- ✧ Haptics
- ✧ Tactile Perception
- ✧ High Precise Control Method
- ✧ Optimizing Bilateral Control

Program Committee Chairs:

Xiaozhen He, Rensselaer Polytechnic Institute, USA

Email: hex6@rpi.edu

Homepage: <http://homepages.rpi.edu/~hex6/>

Bio: He received the B.S. and M.S. degrees in mathematics from Nanjing University, Nanjing, China, in 2000 and 2003, respectively, and the M.S. and Ph.D. degrees in civil engineering from the University of Minnesota Twin Cities, Minneapolis, MN, USA, in 2007 and 2010, respectively. He is currently an Assistant Professor with the Department of Civil and Environmental Engineering, Rensselaer Polytechnic Institute, Troy, NY, USA. He was a PostDoctoral Research Associate with the NEXTRANS Center, Purdue University, West Lafayette, IN, USA. His research interests include transportation systems analysis and modelling, urban traffic management and



operations, intelligent transportation systems (ITS), and interdependent infrastructure systems resilience.

Pengwen Xiong, Nanchang University, China

Email: steven.xpw@ncu.edu.cn

Homepage: <http://users.ncu.edu.cn/~stevenxpw>

Bio: Pengwen Xiong received his B.S. degree from Department of Information Engineering, North University of China in 2009, and Ph. D. degree from School of Instrument Science and Engineering at Southeast University in 2015. He visited Laboratory for Computational Sensing and Robotics, Johns Hopkins University from 2013 to 2014. He is currently a lecturer at the School of Information Engineering, Nanchang University. His research interests include human robot interaction, robotic sensing and controlling.

Xiaorui Zhang, Nanjing University of Information Science & Technology, China

Email: zxr365@126.com

Bio: Xiaorui Zhang received BSc and MSc both from Henan University of Science and Technology in 2004 and 2007, respectively, and she received PhD from Southeast University in 2010. Now she is an associate professor and supervisor for master student in School of Computer and Software, Nanjing University of Information Science & Technology. Her current research interests include human-computer interaction, virtual reality technology and machine vision.

Program Committee:

Xukai Ding, Southeast University, China

Qiang Zhang, Nanchang University, China

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