

Application V1 demo execution shows the expected behavior of the Haptic control software performing bi-lateral coupling between the simulated Virtuoso robot arm and a mobile virtual object (green ball) dynamically simulated on a remote computer running a Physics Engine (currently a simplified version). Because of some technical issues, not all expected Ocera features have been implemented in this application release. The missing features will though be implemented in the final release (V2) that will work with a real Virtuoso robot arm and a full featured Physics Engine application (using Vortex physics engine).