

HANDEXOSKELETONFORREHABILITATIONOFSTRO KEPATIENT

Submitted in partial fulfillment of the requirements for the award of Bachelor of Engineering degree in
Electronics and Communication Engineering

By

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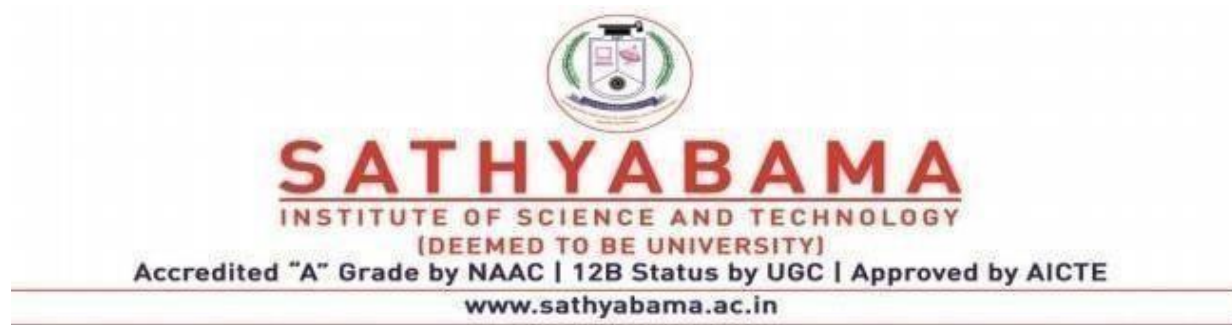


DEPARTMENT OF ELECTRONICS AND COMMUNICATION ENGINEERING

SCHOOL OF ELECTRICAL AND ELECTRONICS ENGINEERING

**SATHYABAMA
INSTITUTE OF SCIENCE AND TECHNOLOGY
(DEEMED TO BE UNIVERSITY)
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JEPPIAARNAGAR, RAJIV GANDHI SALAI, CHENNAI-600119 APRIL –**

2021



DEPARTMENT OF ELECTRONICS AND COMMUNICATION ENGINEERING

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BONAFIDE CERTIFICATE

This is to certify that this Project Report is the bonafide work of ANDHAVARAPUSAISUMANTH (37130022) and ANEGONDI NARENDRA (37130023) who have done the Project work as a team who carried out the project entitled "**HAND EXOSKELETON FOR REHABILITATION OF STROKE PATIENT**" under my supervision from September 2020 to April 2021.

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DECLARATION

We, **ANDHAVARAPU SAI SUMANTH (37130022)** and **ANEGONDI NARENDRA (371300023)** here by declare that the Project Report entitled **“HAND EXOSKELETON FOR REHABILITATION OF STROKE PATIENT”** done by us under the guidance of **MS.J.PREMALATHA(PH.D)**, at Sathyabama Institute of Science and Technology is submitted in partial fulfillment of the requirements for the award of Bachelor of Engineering degree in Electronics and Communication Engineering.

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ACKNOWLEDGEMENT

We are pleased to acknowledge our sincere thanks to **Board of Management of SATHYABAMA** for their kind encouragement in doing this project and for completing it successfully. We are grateful to them.

We convey our thanks to **Dr. N. M. Nandhitha, M.E, Ph.D, Dean, School of Electrical and Electronics** and **Dr.T Ravi, M.E. (Ph.D), Head of the Department, Dept. of Electronics and Communication Engineering** for providing us necessary support and details at the right time during the progressive reviews.

We would like to express our sincere and deep sense of gratitude to our Project Guide **Ms.J.Premalatha (Ph.D)**, for her valuable guidance, suggestions and constant encouragement paved way for the successful completion of our project work.

We wish to express our thanks to all Teaching and Non-teaching staff members of the Department of Electronics and Communication Engineering who were helpful in many ways for the completion of the project.

ABSTRACT

Hand accidents are a frequent problem. The first-rate quantity of hand injuries isn't simplest a problem for the affected humans however economic consequences follow due to the fact rehabilitation takes a long time. physical remedy after an operation is associated with excessive personnel fees. to enhance therapy consequences and decrease value of rehabilitation a hand exoskeleton was developed. The hand exoskeleton changed into mainly designed to accomplish necessities of scientific programs. For studies on manage algorithms and rehabilitation applications a prototype helping all four ranges of freedom of 1 finger changed into build. The tool can be effortlessly connected and also be adjusted to deformed and scarred fingers. In view of the reality that a whole lot of hand injuries affect simplest one finger, this prototype ought to already be functional in physical therapy. This paper presents the construction and the the manipulate machine of the hand exoskeleton and feasible packages in therapy of hand accidents. For the placement control a PID controller become applied and evaluated. The ensuing manage gadget permits following of recorded trajectories with sufficient accuracy.

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Chapter1

INTRODUCTION

1.1 OVERVIEW

Heart Stroke can cause shortage in a variety of neurological areas, but it is especially bad for the motor system. immobility one of the side effect for the body for stroke survivors.. The use of pastime- based approaches to assist the use of immobilised limbs has been shown to fasten the recovery process of the top limb feature in motor rehabilitation studies. As we know human hand **assumes a significant part** in human life it is critical to recover hand movement control after a stroke. Furthermore, the principle situation in the habilitation of the hand motor characteristic has been a way to achieve the most good restoration of hand function. Although several treatments have shown to be effective in stroke patients who have experienced serious, moderate, or minor motor deterioration, a non-obligatory therapy known as bilateral motion training has shown to be effective..

Similarly, bilateral motion exercise has been shown to have a large guarantee in urging upper limb chronic stroke recovery, based entirely on neurophysiological and behavioural mechanisms. In comparison to patients who received unilateral schooling, those who received bilateral schooling showed improved development of higher extremity skills and a reduction in broken limb movement time. The main aim of this paper is to design and develop a stroke rehabilitation device that allows a stroke victim to flex/boom each part of the injured hand based on the flexion/extension motion of the healthy hand palms. Because of the plasticity of the human mind, the hand motor control of the stroke survivor's affected limb can be strengthened by the use of appearing bilateral movement education.

1.2. RESEARCH ON HAND FUNCTION REHABILITATION

The study resulted in the creation of a grip mechanism assistant system for finger rehabilitation that can be leased. As a starting point, the index and thumb fingers were used. Since the index and thumb have a one-of-a-kind extension and flexion motion, as well as a one-of-a-kind collection of bones, it was decided that each finger should have its own mechanism. In other research, a robotics-based therapy method for hand gripping and releasing was developed, which relied solely on the extension and flexion of the fingers. **The gadget utilized a wire-driven system to execute the finger augmentation and flexion motions. The gadget can help dull finger expansion and**

flexion development all through the restoration span. The actuating system of the tool permits the patient to manipulate the motion with the resource of the usage of the self-movement control idea. at the same time as in distinct studies, a hand exoskeleton device has been developed for people who have partially out of place the capability to govern efficaciously the hand musculature. based mostly on EMG indicators the device can recognize the difficulty volition to move the hand and actuators can assist the fingers motion that allows you to perform the task. In the study conducted by Hommel et al, a hand exoskeleton design was created with four stages of freedom for each finger: flexion and extension in the Metacarpophanlangealjoint, proximal inter phalangeal joint, and first knuckle from the top of the finger; and abduction/adduction in the Metacarpophanlangealjoint.

1.3 MODELOFTHEHAND

The human hand has a remarkable range of motion. The kinematical shape of the hand should be modelled in order to model the articulation of fingers. A kinematical version of the hand has been produced. There are 27 degrees of freedom in this kinematical model . Each of the four hands has four degrees of freedom. The metacarpophalangeal (**Metacarpophanlangeal**) joint has DoF due to flexion and abduction, while the distal interphalangeal and proximal interphalangeal (**proximal inter phalangeal**) joints each have one DoF. The thumb has a exclusive shape from the opposite 4 arms and has 5 degrees of freedom, one for the **interphalangeal** joint, and for every of the thumb **Metacarpophanlangeal** joint and trapeziometacarpal joint both because of flexion and abduction. The palms have a total of 21 degrees of freedom. The palm's rotational and translational movements, each with three degrees of freedom, account for the final six degrees of freedom.

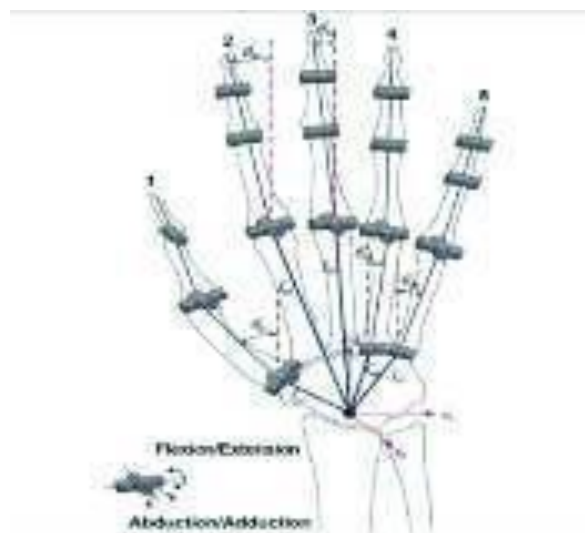


Fig1.1ModelOfTheHand

1.4 HUMAN HAND FINGER MOTIONS

The explanation of the 21DOFs plays out the basic flexion/extension, abduction/adduction, and abduction/adduction of the thumb and fingers. The flexion/extension movements are utilized to clarify pivots toward and away from the palm at any joint in the hand, as seen. The abduction motion is the separation movement (e.g., spreading fingers apart), while the adduction motion is the approximation movement (e.g., folding fingers together). Abduction and adduction occur only at the **Metacarpophalangeal** joints of each finger and the **Metacarpophalangeal** and trapeziometacarpal joints of the thumb. Another two inside DOFs are situated at the base of the fourth and fifth metacarpals (ring and

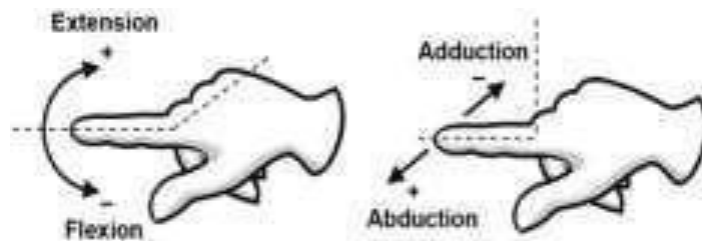
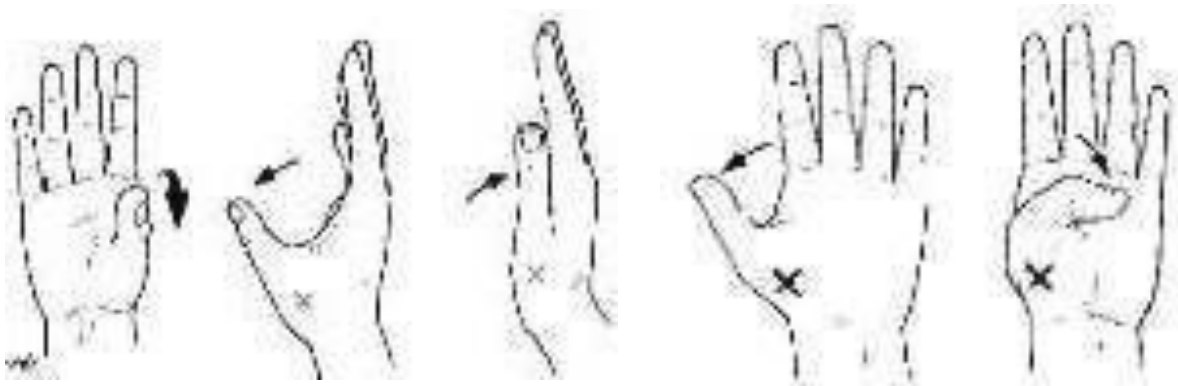


Fig.1.2 Finger Motions (Abduction/Adduction And Flexion/Extension)



little finger), which play out the palm's bend and overlay activities.

Fig.1.3 Thumb Motions (Abduction/Adduction And Flexion/Extension)

As shown in fig.1.3, the thumb abducts and adducts in a plane perpendicular to the hand, while flexing and stretching in a plane parallel to the palm. Our system's design goals are based on human hand morphology, kinematical structure, and constraints.

The system is entirely dependent on the flexion of the fingers. and extension motion and is simple to use, requiring only a **turn OFF or turn ON order and finger** flexion facts, with no need for any verbal communication with a laptop. The computer should be portable (less than 2 Kg). And when wearing the device, the stroke victim must be able to freely pass both hands. The computer must provide at least 15 degrees of freedom to the side (DOFs).

1.5 Design of the Device

The computer has a control hand with 52.2” Flex sensors on each finger of a glove to investigate voltage changes as motion occurs. Arduino is used to connect the system. The Stroke hand has servo motors that are regulated by Arduino based on the results of the manipulate hand in order to rehabilitate the patient..

Chapter2

LITERATURE SURVEY

[1] Christopher L. Jones et al. Design and Development of the Cable Actuated Finger Exoskeleton for Hand Rehabilitation Following Stroke -2014

Following a stroke, finger harm causes huge impedances close by control and the capacity to perform ordinary undertakings. Despite the fact that new progressions in recovery mechanical technology have shown guarantee regarding advancing practical development, it is as yet indistinct how best to utilize those robots to enhance benefits. Bleeding edge hand-held gadgets, then again, do not have the capacity to totally investigate the scope of conceivable instructive standards. They can't give the independent joint control and speed and force organizes that are required.. We've made a model for one digit, the link incited finger exoskeleton (CAFE), a three-level of-freedom robotic exoskeleton for the forefinger, to address this issue. This paper talks about the CAFE's plan and improvement, just as the results of execution testing.

[2] Yili Fu et al. Design and development of a hand rehabilitation robot for patient-cooperative therapy following stroke .2011

Strokes are normal and ordinarily bring about extreme hand weakness. For quite a while, conventional robot frameworks have been conveyed to help with cure and have effectively had a positive effect. Be that as it may, with the progression of treatment techniques as of late, a more popularity for the recovery robot has been proposed. Therefore, we're making the HIT-glove, a stand-out hand recovery robot that will give patient-agreeable treatment to hand-debilitated post-stroke patients. The mechanical plan of the activated hand exoskeleton is nitty gritty in this paper, just as the control technique for patient participation. The impelled hand exoskeleton, which can be appended to arms, all things considered, and shapes, can activate any joint of the fingers reciprocally. The patient-agreeable control approach, which depends on a detecting framework and an intelligent interface, is all around intended to empower the patient to effectively take part in the treatment. In addition, to amplify the impact of deliberate hand recuperation, our robot is relied upon to have the accompanying kinds of treatment: Exercising engine highlights for joints and development Finger coordination training.

[3] R.J.SANCHEZ Et.Al Automated Arm Movement Training Following Stroke: Functional Exercises With Quantitative Feedback in a Gravity-Reduced Environment-2006.

Quite possibly the main objectives of restoration designing is to build up a framework that permits individuals with serious engine debilitations to rehearse arm movement without the requirement for consistent direction by a recovery specialist. This paper discloses how to improve this sort of unit, otherwise called the WREX or ("T-WREX"). An orthosis that guides arm movement in an enormous workspace, a grasp sensor that detects hand hold strength, and programming that recreates valuable undertakings are completely remembered for the machine. The arm orthosis is an instrumented, grown-up measured form of the Wilmington automated Exoskeleton (WREX), a five-phases of-opportunity framework that utilizes versatile groups to latently offset the heaviness of the arm. This paper portrays pilot exploration of T-capacities WREX's in the wake of introducing an exhaustive format clarification of the framework. People with constant stroke whose arm include is debilitated in an ordinary gravity setting will direct achieving and drawing developments by utilizing TWREX, as indicated by the principal study. The subsequent investigation found that practicing the influenced arm of five individuals with ongoing stroke with T-WREX for about two months improved unassisted movement potential (mean change in Fugl-Meyer rating was five elements plusmn 2 SD; mean change in scope of movement of coming to was 10%, $p < 0.001$). These discoveries exhibit that utilizing detached gravity help, a hold sensor, and straightforward advanced truth devices, it is feasible to robotize upper extremity recovery treatment for individuals with serious stroke.

[4] Design and control of an actuated thumb exoskeleton for hand rehabilitation following stroke
Furi Wang Et.al., 2011

Following a stroke, ongoing hand injury is ordinary. An activated thumb exoskeleton (ATX) is introduced in this paper to help concentrate close by recovery treatment. Utilizing a framework with five dynamic DOF and three aloof DOF, the ATX gave in this work permits autonomous bi-directional incitation in every one of the thumb's five scopes of-opportunity (DOF). The ATX will give the client huge joint forces while likewise taking into consideration drivability on account of the flexible shaft transmission. A model was fabricated, and tests were done to assess the shut circle job control. Likewise, work on creation and destiny is tended to.

[5] Control and Kinematic performance analysis of an Actuated Finger Exoskeleton for hand rehabilitation of stroke Christopher L.Jones Et.al., -2010

Following a stroke, finger harm causes a critical loss of hand control and the capacity to perform typical assignments. Restoration adequacy has improved because of late advancements in recovery mechanical technology. Notwithstanding, current machines do not have the capacity to interface with the human finger at paces and forces that are tantamount to the general effectiveness of every day hand control undertakings. We built up the Actuated Finger Exoskeleton (AFX), a three-level of-opportunity robot exoskeleton for the indexfinger, to address this issue. The AFX's execution and starting kinematic assessment are depicted in this paper.

[6] An Actuated Finger Exoskeleton for Hand Rehabilitation Following Stroke T.T.WorsnoppEt.al., -2007

Following a stroke, it is entirely expected to encounter perpetual hand debilitation. In spite of the fact that mass development practice has shown guarantee in recuperation, the hand's underlying incapacity might be too extreme to even consider empowering evenapproximations of the ideal development. We're assembling an exoskeleton to empower unbiased incitation of every one of the three joints of the pointer to make development simpler, especially squeezing. For flexion and augmentation, separate actuators are utilized, with shut circle control of both pressing factor and capacity. Later on, a thumb exoskeleton might be created to empower synchronized squeezing. This technique might be utilized to test systems for improving squeeze and achieve squeeze recuperation after a stroke. The incited forefinger exoskeleton idea is accessible here.

[7] Subject-Specific Assist-as-Needed Controllers for a Hand Exoskeleton for Rehabilitation PriyanshuAgarwal, Ashish D. Deshpande-2018

Mechanical palm restoration after a neuromuscular weakness or stroke requires regulators that can give trouble explicit help and accelerate the recuperation cycle. We show two such assistance as-wishregulators for the Maestro hand exoskeleton, which is intended to give exact force help to a subject. found pressing factor subject control is an uncommon control procedure where a neural-based regulator is An organization based absolute model of the essential forces is found disconnected for a particular issue and afterward used to make a power field to help the finger development in after an objective direction. Versatile help depending on the situation control, then again, utilizes an outspread establishment trademark (RBF) gathering to assess the coupled finger-exoskeleton contraption force necessity of a subject and changes the RBF sizes progressively to give feedforward help to exact direction following. Analyses on Maestro with a

sound trouble showed that while the power subject control is non-versatile and there is undeniably less command over the speed with which the task is executed, it is a lot more secure on the grounds that it doesn't submit to raised forces if the finger development is limited. Versatile assistance as-wish regulator, then again, adjusts to the changing requirements of the coupled finger-exoskeleton framework and permits the undertaking to be completed at a consistent speed, yet it applies expanded forces in compelled development and is in this manner without a doubt substantially less secure.

[8] Sliding mode control of an exoskeleton robot for use in upper-limb rehabilitation Mahdieh Babaiasl Et.al., 2015

Mechanical engineering and control of an exoskeleton robot for shoulder restoration after stroke are introduced in this paper. The mechanical plan of another three levels of opportunity (DOF) exoskeleton automated for shoulder joint recovery is introduced first. All robot estimations depend on the properties of a person's upper appendage, regardless of whether male or female. For the 1/3 joint, another open roundabout instrument is proposed. From that point forward, the immediate and backwards kinematics, Jacobian network, particular focuses, and mechanical elements are examined. Sliding mode regulator (SMC) is proposed to music supported directions to inspect the robot's capacity to comply with the improved directions. Since the mechanical engineering of most restoration robots is the center, straight controls are utilized to work the robot. Restoration robots, then again, are non-direct in plan, requiring non-straight control strategies that can dismiss vulnerabilities and are resistant to boundary changes. On account of its nonlinear nature, SMC is amazing, and it can dismiss vulnerabilities and aggravations utilizing the gadget, which incorporates the influenced individual's hand quake. The SMC's boundaries are calibrated utilizing a hereditary calculation (GA). Low weight, an extraordinary component for the 1/3 joint that tends to the realized issues related with long wiring and shut instruments, permitting translational levels of opportunity of the shoulder, convenience, solace for the influenced individual, and controlling by and large execution of the regulators are the primary benefits of this mechanical contrasted with comparable frameworks. [9] Robotic unilateral and bilateral upper-limb movement training for stroke survivors afflicted by chronic hemiparesis

[9] Matt Simkins; Hyuchul Kim; Gary Abrams; Nancy Byl, Jacob Rosen-2013

Stroke is the main source of long haul neurological insufficiency and the most widely recognized justification looking for rehabilitative administrations in the United States. While learning-based restoration preparing helps most stroke patients to recapture free versatility, recuperation of fine control, engine qualities, and undertaking explicit elements of the hemiplegic arm and hand is referenced in under 15% of stroke patients.

The inherent instrument that takes into consideration the recuperation of engine abilities by neurological rearrangement of the cerebrum in light of appendage incitement is known as psyche pliancy. The point of this investigation was to perceive how well a twin arm exoskeleton gadget (EXO-UL7) may recuperate the upper appendages utilizing three distinct modalities: two-sided reflect picture with symmetric developments of the two arms, one-sided development of the influenced arm, and inescapable treatment. Every treatment methodology was apportioned to five hemiparetic subjects indiscriminately. A top appendage exoskeleton got used to give respective and one-sided cures. favored consideration become outfitted through an approved substantial advisor. Themes had been assessed sooner than and after the intercessions the utilization of 13 exceptional clinical measures. Following these medicines, the entirety of the members showed huge enhancements in their fine engine control and gross control in all treatment modalities. For respectivepreparing and favored treatment, subjects showed huge changes in shoulder assortment of development and bulk, yet not for one-sided tutoring. To sum up, a synergetic methodology wherein robot medicines (one- sided and respective relying upon the degree of engine control) are enhanced by standard of care may likewise expand the results of engine control recuperation following stroke.

Chapter3

AIM :-

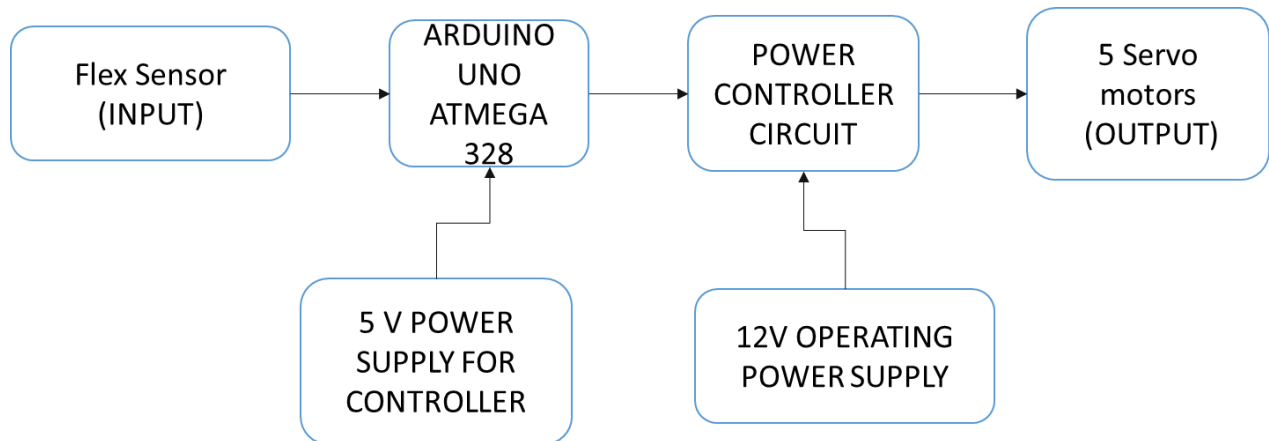
In this gadget ,we are using arduino UNO 328 which acts as brain of the machine, due to the fact the whole gadget program training saved in it and also flex sensors that is used to send inputs to the arduino relying at the hand movement and after that the machine gives the enter to the servo motors.And servo cars rotate accordingly to relax the hand.

3.1 EXISTINGSYSTEM

In arduino UNO, the set of rules is very complex due to the fact right here we're using programming i/p instead of replicator. whenever the angles adjustments from the replicator theArduino senses the angleadjustments and gives mechanical control output to the servo automobiles.

3.2 PROPOSEDSYSTEM

The control glove's aim is to give user command on their incapacitated fingers by moving the hands. On the off chance that you need pockets in each finger so the flexsensors can be set into them, utilize a uniquely crafted hand glove as a flexion or expansion move inside.



3.1FigureBlockdiagram ofProposedSystem

The sensor is hooked up to an Arduino microcontroller for analogue sign detection. To read the sensor, its

variable resistance is **changed to a variable voltage and intensified with an operation amp**. The data could be used to govern servo automobiles which flow the patient manipulate glove. Every of the patient fingers will flow in addition to the flexion of flex sensor attached at the clever Glove. Preliminary experiments were completed to decide the characteristics of a flex sensor before being connected on the smart Glove.

HARDWARE AND SOFTWARE USED

3.3 EMBEDDED SYSTEMS

3.3.1 OVERVIEW OF EMBEDDED SYSTEMS

An implanted PC is a solitary reason PC that is customized to perform one or a couple of explicit assignments, regularly with ongoing figuring limitations. It is frequently utilized as a component of a total apparatus, which incorporates equipment and mechanical parts. A favored reason PC, like an individual PC, then again, can play out a wide scope of errands utilizing programming. Inserted frameworks have come to be pivotal these days as they control a portion of the normal gadgets we use for the explanation that implanted machine is committed to explicit commitments, plan architects can advance it, bringing down the size and cost of the item, or developing the dependability and generally speaking execution. Some inserted frameworks are modernly delivered, capitalizing on economies of scale truly, implanted frameworks range from versatile devices like advanced watches and MP3 gamers, to enormous fixed establishments like guests lights, fabricating office regulators, or the designs controlling atomic power greenery. Intricacy differs from low, with an unmarried microcontroller chip, to extremely high a few units, peripherals and organizations mounted inside a tremendous undercarriage or fenced in area.

When all is said in done, "implanted PC" doesn't allude to a particular time frame since numerous gadgets have some programmability. Handheld PC frameworks, for instance, share a few components with implanted frameworks — which incorporate the working frameworks and chip that power them — yet they aren't genuinely inserted structures since they take into consideration the stacking of novel projects and the association of peripherals. Installed frameworks can play out an assortment of errands.

Screen the climate: Data from input sensors is deciphered by installed frameworks. The information is then dissected, and the outcomes are appeared to a client or clients in some arrangement.

Control the climate: Instructions for actuators are delivered and communicated by installed frameworks.

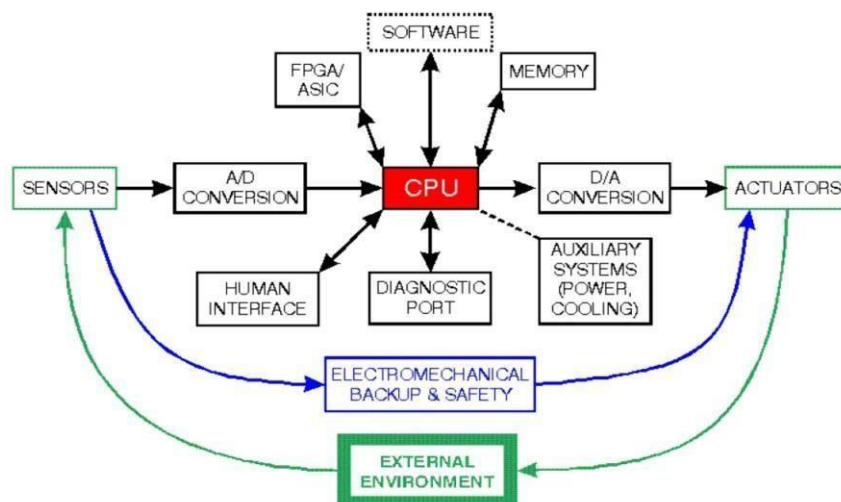
While connection with the rest of the world through sensors and actuators is a noteworthy piece of installed frameworks, these frameworks regularly gives abilities clearly to their apps. Implanted frameworks are regularly used to run apps, lets say control rules, finite state machines, and sign handling computation. These frameworks should alsodistinguish and also react to flaws in both the inside registering climate and the encompassing electromechanical frameworks. There are a few sorts of inserted structures, going from specialized gadgets to domestic devices that handle structures. Specialized gadgets, for example, modems and mobile phones, just as home devices, are models.

e.g.: Structures are constrained by CD players, VCRs, and microwaves.

e.g.: Anti-lock slowing mechanisms in autos, robots, and satellite TV for PC control

BLOCKDIAGRAMOF ANEMBEDDEDSYSTEM:

An inserted processor is generally utilized in an implanted gadget. Inserted gadgets are utilized in many home machines with a computerized interface, like microwaves, VCRs, and engines. A running framework is utilized in some installed structures. Others are profoundly specific, bringing about the whole presence of mind being executed as a solitary program. Aside from giving basic reason figuring, these frameworks are implanted into some PC for some particular explanation. In this image, a run of the mill installed machine is



appeared.

Fig3.2Blockdiagramofatypicalembeddedsystem

3.3.2 CHARACTERISTICS OF EMBEDDED SYSTEMS

Inserted frameworks are recognized by a particular assortment of qualities. Installed machine creators were exposed to an extraordinary arrangement of design limitations because of and of these attributes. The assignment of planning inserted frameworks is to stick to the utility's remarkable arrangement of limitations.

3.3.3 APPLICATION SPECIFIC SYSTEMS:

Inserted frameworks aren't just about as well known as work stations. The plans of implanted devices are customized to a particular application. Most of assignment qualities are recognized before the equipment is planned. This opens up the style creator to zero in on the particular plan imperatives of an all around characterized utility. Thus, client reinventing limit is restricted. Notwithstanding, certain installed structures require the capacity to reconstruct in an adaptable way. For such projects, programmable DSPs are well known

3.3.4 REACTIVE SYSTEMS

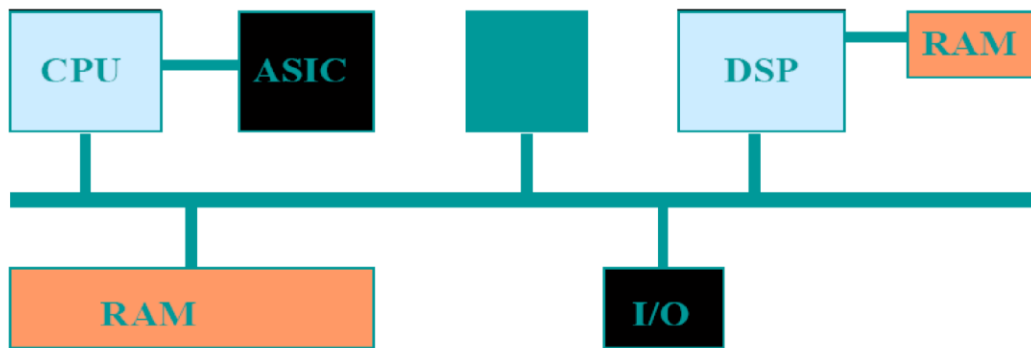
A run of the mill inserted structures rendition, as recently referenced, reacts to the climate through sensors and deals with the climate through actuators. This requires implanted frameworks running at a similar rate as their environmental factors. The expression "responsive" depicts this component of inserted gadgets. Receptive calculation signifies that the gadget (for this situation, the product program segment) reacts to outside events. Outside events might be either customary or unpredictable. Occasional undertakings make it simpler to design handling so in general proficiency is kept up. Aperiodic occasions are more hard to plan. The most noteworthy event arrival rate ought to be anticipated to represent most pessimistic scenario situations. Most of installed frameworks have an enormous responsive factor. Quite possibly the most troublesome assignments for inserted framework fashioners is to direct an exact most pessimistic scenario configuration concentrate on gadgets with factual execution qualities (e.g., reserve memory on a DSP or other implanted processor (real-time)). The rightness of a computation is reliant, to a limited extent, on the time at which it is applied to the framework. Constructions that would meet this rule ought to be intended for the most dire outcome imaginable. On complex designs, nonetheless, accurately anticipating the most pessimistic scenario can be troublesome. This occasionally brings about exorbitantly mindful gauges that decide in favor alert. Many installed frameworks have a popularity for continuous activity to deal with outside I/O and equilibrium necessities. Countless continuous frameworks are likewise responsive designs.

3.3.5 DISTRIBUTED SYSTEMS

Talking techniques running on different CPUs or ASICs that can be associated through verbal exchange hyperlinks are a commonplace segment of embedded machines. The fact of the matter is to improve the monetary structure. Four eight-bit microcontrollers that are sensibly assessed can be more affordable than 32-cycle processors. Also when the meaning of the conversation ties is determined in, this system could be the marvelous. Different processors are ordinarily needed in this manner to manage address distinctive time-essential commitments. Devices constrained by embedded systems can moreover be controlled significantly.

3.3.6 HETEROGENEOUS ARCHITECTURES

Inserted frameworks are regularly comprised of divergent models (Fig 1.2). Various processors will be



utilized in a similar gadget arrangement. They'll be blended sign frameworks too. The mix of I/O interfaces, close by and far away recollections, just as sensors and actuators, brings about a profoundly point by point installed computer configuration. Implanted frameworks are hence compelled as far as design, and heterogeneity allows for more layout versatility.

Fig3.3 Embedded Systems having Heterogeneous Architectures

3.3.7 HARSH ENVIRONMENT

Many installed frameworks don't work in a controlled climate. Warmth is commonly a torment, especially in programs that include burning (e.g., numerous transportation bundles). Extra issues for implanted figuring can be brought about by an absence of security from vibration, shock, lightning, power supply vacillations, water, rust, hearth, and regular real viciousness.

SYSTEM SAFETY AND RELIABILITY

Installed contraptions are beginning to misuse increasingly more of the overall framework's wellbeing perspectives as their complexity and computational force increment. These safety efforts may appear as programming or equipment control. Mechanical insurance reinforcements are often initiated when the PC

gadget fails to keep a grip on the cycle of totally closing down the machine. The issue of programming program security and trustworthiness has gotten more extreme. By and large, programming doesn't "crush" into the vibe of equipment. Nonetheless, programming can be intricate to such an extent that a progression of unforeseen occasions can trigger programming mistakes, bringing about risky circumstances.. exchange of this theme is outside the extent of this digital book, yet the difficulties for installed creators incorporate planning dependable programming project and building modest, accessible frameworks the utilization of untrustworthy added substances. the essential undertaking for implanted machine creators is to procure low- esteem unwavering quality with least excess.

3.3.8 CONTROL OF PHYSICAL SYSTEMS

quite possibly the main thought processes in inserting a PC is to collaborate with the environmental factors. that is as often as possible completed through following and controlling outside gear. Inserted PCs change the simple markers from sensors into computerized structure for handling. Yields should be changed lower back to simple sign levels. while controlling real gadget, huge current burdens may furthermore should be exchanged in order to work vehicles and various actuators. to fulfill those cravings, installed constructions may require large computer circuit sheets with numerous non-virtual added substances. Installed gadget planners need to circumspectly adjust gadget tradeoffs among simple added substances, strength, mechanical, local area, and computerized equipment with relating programming.

3.1.10 SMALL AND LOW WEIGHT

Many implanted PCs are truly situated inside some bigger framework. The structure factor for the implanted framework might be directed by style. Some of the difficulties of installed frameworks fashioners ate to create non-rectangular calculations for specific arrangements. heaviness can likewise be a basic limitation .Embedded vehicle control frameworks, for instance, should be less heaviness for mileage. Portable CD players should be light weight for movability purposes.

3.1.11 COST SENSITIVITY

Expense is an issue in many designs, yet the affectability to esteem adjustments can run drastically in installed structures. that is explicitly because of the effect of pc costs have on benefit and is more prominent a component of the portion of value changes when contrasted with the whole gadget esteem.

3.1.12 POWER MANAGEMENT

Inserted structures have exacting limitations on power. Given the conveyability necessities of

numerous

installed structures, saving power is imperative to keep battery life as long as plausible. Reducing of the warmth creation is some other clear circumstance for implanted frameworks.

3.4 POWERSUPPLY

Power supply consists of four parts they are transformer,rectifier,filter,regulator these four parts are combined together to supply a constant Direct Current(DC) voltage across the load

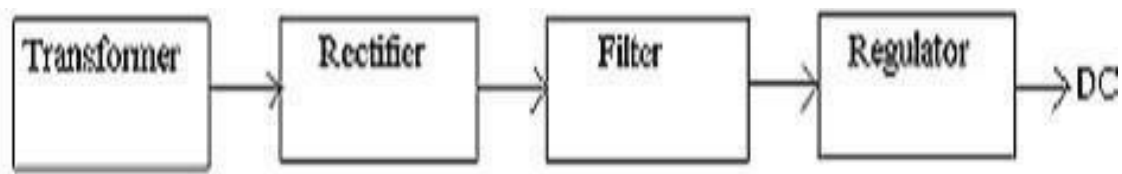


Fig3.4General BlockOfPowerSupplyUnit

3.5 TRANSFORMER:

Transformer is a passive electrical device which is used to transfer electrical energy from one circuit to another by using electromagnetic Induction. Transformer is used everywhere it is mainly used for its property to increase or decrease the electrical energy in the circuits.

3.6 RECTIFIER :

Rectifier is a passive electrical device that is used to convert a two directional Alternating(ac) current to one Directional Alternating Current.there are two types of rectifiers they are

- 1.Single Phase
- 2.Three Phase

Theres also half wave rectifier and full wave rectifier

3.7 FILTERS:

There are different types of filters there are active filters and also passive filters

Filter is known as a passive filters if the component are combination of passive elements and its know as

active filter if the components are combination of active elements.

Filters uses depends completely on the field we are working on.If we are working on signal processing filter is used to take out the unwanted components in same way in electrical side it is used to block the ac Rectifier and allows only dc load.

There are different types of filters,They are

- 1.High pass filter
- 2.Low pass filter
- 3.Band pass filter

3.7 REGISTERS:

Basically registers are used to store the data for a limited time.these registers are widely used in the embedded systems,There are different types of registers they are

- 1.Accumulator
- 2.R register
- 3.B register
- 4.Data pointer
- 5.Program counter
- 6.Stack pointer

3.9 REGULATORS:

Regulator is an electrical or electronic device that is used to maintain the voltage in required range .These regulators are required to maintain the voltage there are different types of regulators they are active regulators and also passive regulators .If a regulator contains a combination of active elements it is known as active regulator in the same way if the regulator contains a combination of passive elements its known as passive regulator

CHAPTER 4

FLEXSENSOR

A simple flex sensor 2.2" long. As you twist the sensor (flexing), the opposition all through the sensor increments.

The resistance of the flex sensor changes while the metallic pads are on the outside of the bend (text on inside of bend).



Figure 4.1 Flex Sensor

A polymer ink with conductive particles is written on one side of the sensor. where the sensor is promptly, the trash convey the ink an obstruction of roughly 30k Ohms. while the sensor is bowed distant from the ink, the conductive garbage flow correspondingly separated, expanding this protection from (roughly 50k Ohms while the sensor is adapted to ninety°). while the sensor fixes again, the opposition gets back to the first expense. by utilizing estimating the opposition, you may determine how tons the sensor is being twisted.

The least complex approach to include this sensor into your test is through the utilization of it in a voltage divider. This circuit requires one resistor. Numerous qualities from 10K to 100K will compositions, yet we'll utilize a 10K resistor here. join the flex sensor to your microcontroller the utilization of the ensuing circuit.

WORKING

One side of the sensor is printed with a polymer ink that has conductive particles installed in it. while

the sensor is promptly, the trash convey the ink an obstruction of roughly 30k Ohms. while the sensor is

bowed distant from the ink, the conductive garbage flow correspondingly separated, expanding this protection from (roughly 50k Ohms while the sensor is adapted to ninety°). while the sensor fixes again, the opposition gets back to the first expense. by utilizing estimating the opposition, you may determine how tons the sensor is being twisted.

The least complex approach to include this sensor into your test is through the utilization of it in a voltage divider. This circuit requires one resistor. Numerous qualities from 10K to 100K will compositions, yet we'll utilize a 10K resistor here. join the flex sensor to your microcontroller the utilization of the ensuing circuit.

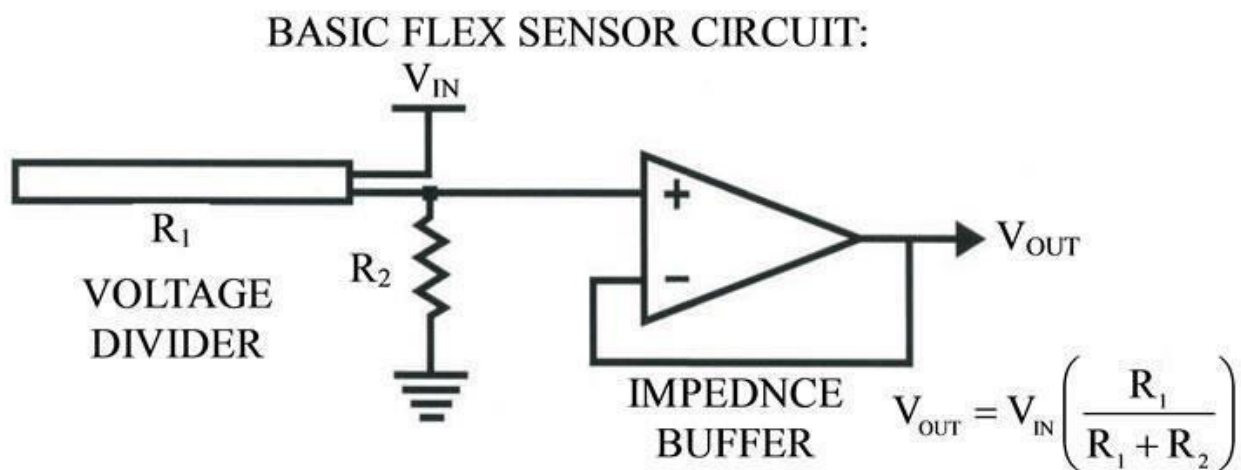


Fig4.2BasicFlexSensorCircuit

go along with one side of the flex sensor to floor. interface the contrary side for your simple information, and use a 10K pullup resistor to VCC.

The resistor and the flex sensor structure a voltage divider, what partitions VCC through a proportion determined by the two protections. at the point when the sensor is quickly, the 10K resistor and the 30K flex sensor will rationale the yield voltage to be around 75 level of VCC. at the point when the sensor is twisted, the voltage will increase to around 83 level of VCC . in case you're utilizing 5V for VCC, you should see about three.75V while the sensor is quickly, and around 4.17V while the sensor is twisted by utilizing ninety°.these numbers will differ for singular sensors; for the greatest correct results, test your exact sensor and utilize the ones numbers on your code.The sensor works just in one course: while it's far twisted away from the side

with the conductive ink (nearer to the side with the printed content). you may see a little reaction when twisting the distinctive way, anyway not nearly as a lot as in the "exact" way. (in the event that you need to degree bowing in both rules, remember utilizing two sensors once more to-again).these sensors work five star (and shutting the longest) in the event that they're bowed across a major sweep, not, at this point wrinkled. recollect that the dynamic region is among the dark squares. The pin-quit of the sensor is in danger of wrinkling and inevitable disappointment. it's far protected to agreeable this area all together that it would not flex along with the unwinding of the sensor.

ARDUINO

Arduino is an Electronic Device embedded with both hardware and software. Arduino is used to receive input from external sources like sensors .The receive the input from the sensors and this input is used to reflect some other external devices like led,servomotors.This Arduino has a microcontroller,this microcontroller is the head of the Arduino.This microcontroller is used to store the program.we can write a program to control the working of arduino .To upload a program into microcontroller we need arduino ide software.There are different types of arduinos there are

- 1.Arduino uno.
- 2.Red board Arduino
3. Lily pad Arduino

ARDUINO UNO SPECIFICATION

Microcontroller	ATmega328P
Operating Voltage	5V
Input Voltage (recommended)	7-12V
Input Voltage (limit)	6-20V
Digital I/O Pins	14 (of which 6 provide PWM output)
PWM Digital I/O Pins	6
Analog Input Pins	6
DC Current per I/O Pin	20 mA

Flash Memory	32 KB (ATmega328P) of which 0.5 KB <u>used by</u> bootloader
SRAM	2 KB (ATmega328P)
EEPROM	1 KB (ATmega328P)
Clock Speed	16 MHz
LED_BUILTIN	13
Length	68.6 mm
Width	53.4 mm
Weight	25 g

BLOCK DIAGRAM

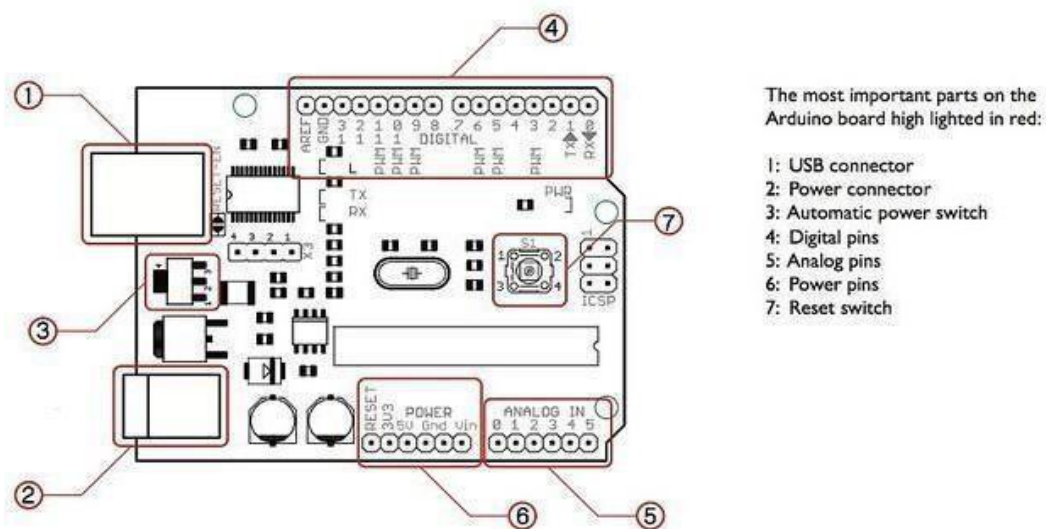


Fig4.3 ArduinoBlockDiagram

Arduino is not difficult to use and also it is widely used by everyone. These Arduino boards are also

used for entertainment purpose. Arduino can be used by everyone and its price also not too high and also arduino software is free of cost. Arduino software IDE known as integrated development environment is a software that is used to upload the program to Arduino. We can download the Arduino ide software from official Arduino website. There will be a guide for the students who are using the Arduino for the first time.

This guide tells us how to use Arduino uno . Arduino uno is a lot better for starters. By uploading a program into Arduino we can create an interface circuit to read sensors etc... and from the input of these sensors we can control the external elements like servo motor, Led.

If you know C and C++ it is much easier to write Arduino program. Even if you don't know C and C++ its not a problem just need to learn basic commands.

A significant element of the Arduino is that you can make a control program on the host PC, download it to the Arduino and it will run consequently. Eliminate the USB link association with the PC, and the program will in any case run from the top each time you press the reset button. Eliminate the battery and put the Arduino board in a storeroom for a half year. At the point when you reconnect the battery, the last program you put away will run. This implies that you associate the board to the host PC to create and investigate your program, yet whenever that is done, you presently don't require the PC to run the program. The Arduino UNO is a miniature regulator board dependent on the ATmega328. It has 14 advanced information/output pins (of which 6 can be utilized as PWM outputs), 6 simple data sources, a 16 MHz crystal resonator, a USB association, a power jack, an ICSP header, and a reset button. It contains all that expected to help the miniature regulator; basically interface it to a PC with a USB link or force it with an AC-to-DC connector or battery to begin. The UNO varies from all first sheets in that it doesn't utilize the FTDI USB-to-serial driver chip. All things being equal, it includes the Atmega16U2 (Atmega8U2 up to variant R2) customized as a USB-to-serial converter.

SERVO MOTOR

A servomotor is a rotational actuator or straight actuator that considers explicit control of position or direct limit, speed and speed increment. It incorporates a fitting engine coupled to a sensor for position comments. It additionally requires an especially modern regulator, routinely a submitted module planned specifically to be utilized with servomotors.

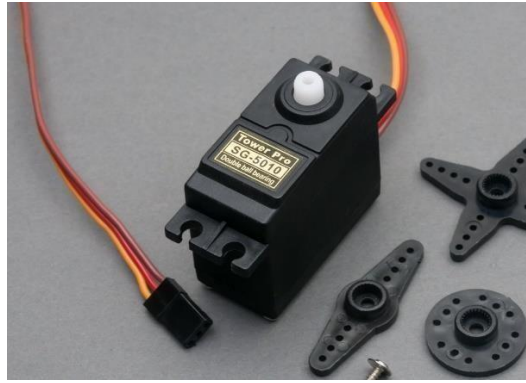


Fig4.4 Servo Motor

Servo engine is work controlled engine. it can without trouble oversee actual movement of items as a result of its capacity oversaw trademark. Servo engine can't move ceaselessly. Servo vehicles turn in heavenly messenger going from zero to one hundred eighty certificate. Servo engine have numerous bundles in advanced mechanics and industry for work based movement control device. rather than various cars, servo engine might be spotless to interface with Arduino or some other microcontroller because of its inherent regulators.

Servo engine can not pass with relentless development until remarks potentiometer is snared. H-connect is utilized to pivot engine either in clock shrewd or hostile to clock reasonable course. So the fundamental increase of servo engine is that it doesn't need any interfacing circuit. in any case, the principle disadvantage of servo engine is its lower speed and espresso energy impediment in contrast with various autos.

WORKING OF A SERVO MOTOR

The Servo Motor basically incorporates a DC Motor, a hardware framework, a job sensor and a control circuit. The DC vehicles get fueled from a battery and run at over the top speed and periodic force. The Gear and shaft get together identified with the DC vehicles decline this speed into adequate speed and higher force. the position sensor detects the arrangement of the shaft from its exact job and feeds their information to the control circuit. The control circuit subsequently unravels the cautions from the position sensor and thinks about the genuine capacity of the vehicles with the favored position and in this way controls the heading of revolution of the DC engine to get the ideal job. The Servo Motor ordinarily calls for DC supply of 4.8V to 6 V.

CONTROLLING OF SERVO MOTOR

A servo engine is constrained by utilizing controlling its job utilizing Pulse Width Modulation approach. The width of the heart beat completed to the engine is various and send for a fixed measure of time.

The beat width decides the precise capacity of the servo engine. for example a heartbeat width of 1 ms causes a rakish capacity of 0 levels, while a heartbeat width of two ms reasons a precise width of one hundred eighty levels.

Advantages

If a heavy load is placed on the motor, the motive force will boom the present day to the motor coils as it tries to rotate the motor. essentially, there is no out-of-step circumstance.

excessive-speed operation is possible.

Disadvantages

Since the servomotor endeavors to turn with respect to the request beats, yet slacks at the back of, it is not suitable for precision control of upset.

Higher cost.

At the point when halted, the engine's rotor keeps on moving to and fro one heartbeat, so it is not reasonable in the event that you need to forestall vibration.

Applications of Servo Motors

Servomotors are utilized in programs requiring rapid variants in pace without the engine getting overheated. In Industries they're utilized in machine instruments, bundling, plant computerization, material managing, printing changing over, gathering follows, and a lot of other requesting applications advanced mechanics, CNC hardware or mechanized manufacturing. they're likewise utilized in radio controlled planes to oversee the situating and development of lifts. they're used in robots because of their smooth turning on and rank and precise positioning. they're likewise utilized by aviation undertaking to keep pressure driven liquid in their water powered frameworks. they are utilized in many radio oversaw toys. they're utilized in computerized devices comprising of DVDs or Blue beam Disk gamers to increment or replay the plate. they're additionally being utilized in vehicles to hold the speed of vehicles.

Application Circuit of Servo Motor

From under programming circuit: each engine has three data sources: VCC, floor and an occasional rectangular wave sign. the heartbeat width of the square wave decides the speed and course of the servo vehicles. For our situation, we just need to change the course to allow the gadget to move forward, in reverse

and turn left and right. In the event that the beat width is under a positive time span, the engine will pressure in a clockwise course. On the off chance that the heart beat width surpasses that point body, the engine determination a counterclockwise way. The middle time period might be changed through an implicit potentiometer inside the engine.

Differences between Stepper Motor and Servo Motor:

Stepper cars have a huge scope of posts, attractive sets created through a lasting magnet or an electric flow. Servo vehicles have a couple of posts; each post offers a natural stepping point for the engine shaft.

The force of a stepper engine at low velocities is extra than a servo engine of a similar length.

Stepper engine activity is synchronized by utilizing order beat markers yield from the pulse generator. In evaluation, servomotor activity slacks at the rear of the order beats.

4.2.8 Arduino Interface with Servomotor

Servo cars are exceptionally perfect to interface with Arduino in light of the fact that it have coordinated engine regulators. So we need least difficult three pins to interface servo engine with Arduino. strength pin, floor pin and pulse signal pin. i'm ready to talk around signal pin in later piece of this content. license's discussion more about servo motor built-in regulator. Servo engine incorporates following segments or in different expressions whole servo motor package incorporates following parts:

Pinion wheels is utilized to control work in levels

Yield shaft is utilized to interface with actual things Potentiometer for work feed once more

heartbeat to voltage converter for remarks voltage to potentiometer

H scaffold to control the arrangement of engine clock astute or hostile to clock keen Comparator make with speaker

Servo engine answer to exchange term of heartbeats. A beat of span 1 milli second explanation the servo engine to move one quit and length of two milli second thought process the engine to move diverse stop. So we can figure servo engine position through different the time of heartbeats to servo with the help of Arduino Uno R3. Arduino IDE have coordinated library for servo engine oversee. so you don't need to compose protracted code for servo engine. You simply need to name include used in servo.h library.

ARDUINO SOFTWARE

The Arduino IDE is a free software, so anyone can use this software in this software we use embedded c for coding, and this software is user friendly and the user can check the output readings in a serial monitor. This Arduino IDE software only interfaced with Arduino micro-controller boards.

The IDE contain a code editor where the user can write the code and check for errors than the user need to check the port is connected or not then upload the code to Arduino micro-controller board.

Stage 2: down load Arduino IDE programming.

you may get phenomenal varieties of Arduino IDE from the download page at the Arduino dependable site.

You need to choose your product program, that is very much coordinated with your functioning contraption (home windows, IOS, or Linux). After your report download is entire, unfasten the report.

when the circuit has been made at the breadboard, you'll need to transfer the program (recognized asa personification) to the Arduino.

The Arduino IDE, design or convey the ideal USB drivers and furthermore the basic arrangement of the IDEfor the Arduino board to be analyzed through the IDE. on this scholastic, we can protect with the ArduinoIDE through investigating its capacities, information the central activity and transferring our first program tothe Arduino UNO board.

sooner than expecting likewise with the instructional exercise, associate Arduino UNO board to the PC through the USB link as demonstrated inside the under picture and pick the right board and COM port in the event that it is notdone as of now. there's no requirement for any outer strength convey to the Arduino board since it draws thenecessary power from the USB association.

The bundles in Arduino environmental factors are called as Sketches. The animation is a fixed of directions that mentions to the board which capacities it wants to do. An Arduino load up can just keep and perform each animation in turn. The product used to make Arduino portrays is known as the IDE which represents joined

DevelopmentEnvironment.

each Arduino exaggeration has key segments to the program:

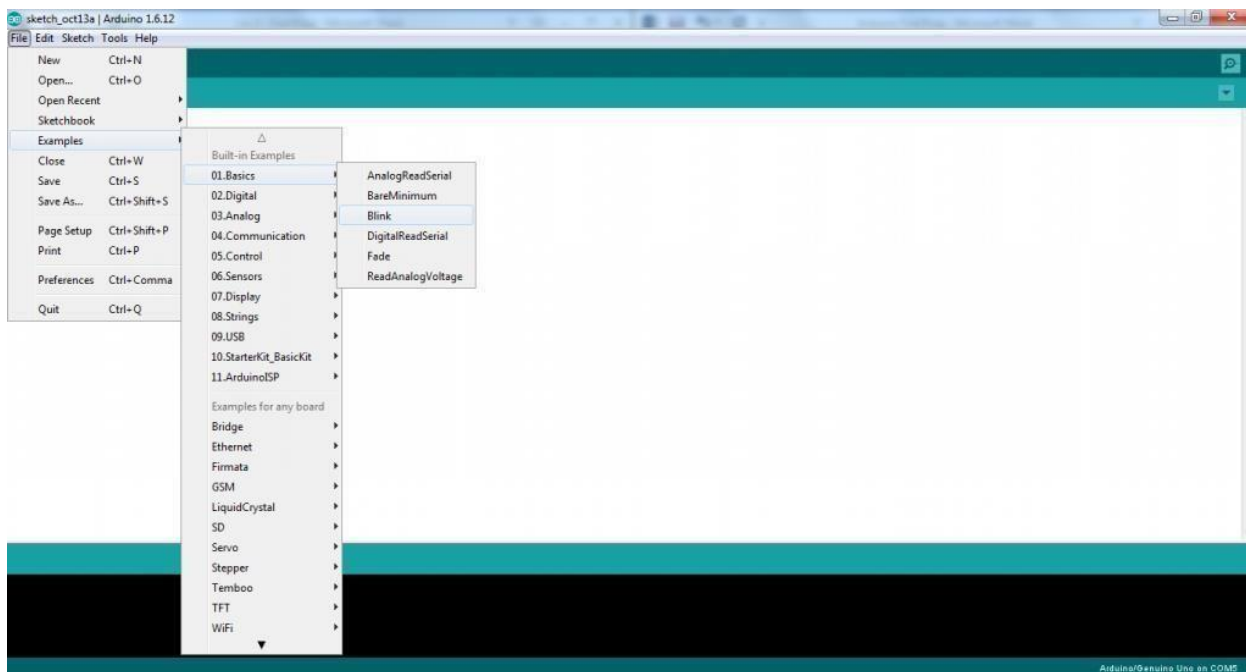
void arrangement() – sets matters up that should be done once after which don't show up once more.

void circle() – fuses the orders that get rehashed time and until the load up is developed to get off.

in the Arduino IDE, the void area featured inside the image under is alluded to as literary substance Editor.This territory can be utilized for composing all the code for our Arduino sheets.



sooner than leaping out with joy and composing our own personal program, we would first be able to investigate a model funny cartoon gave in the Arduino IDE. For this, we need to go to the "record" menu and visit the "Models" tab. in the drop down menu of the Examples tab, we can see a rundown of properlycategorized models like essential, Analog, virtual, correspondence, etc.

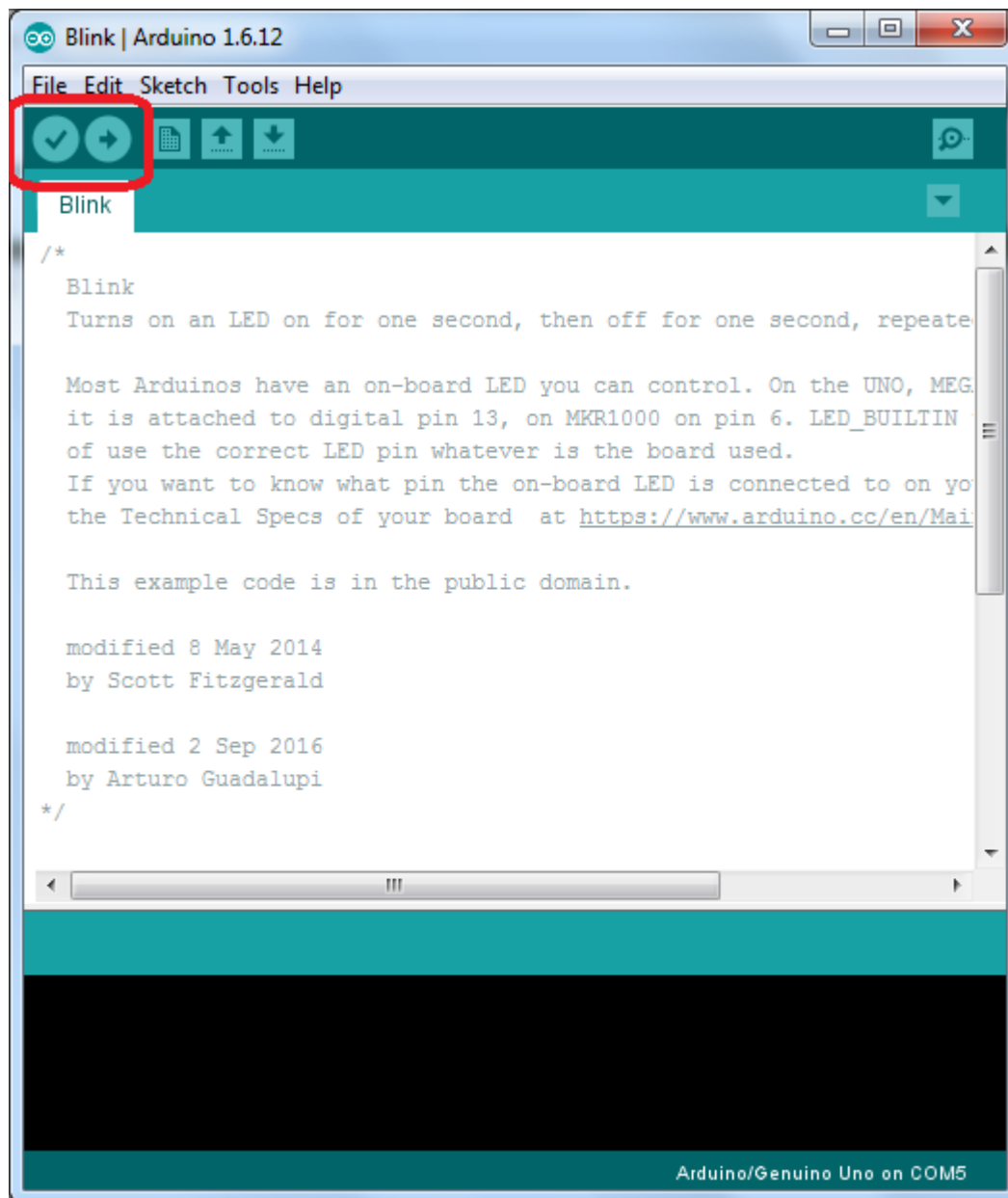


As a beginner or first time client, utilize the essential models and in that pick the "Squint" personification. a pristine window could be opened with Blink exaggeration in it. the utilization of the Blink funny cartoon, we're going to turnON the LED connected to thirteenth pin of the Arduino for one 2d and turn it OFF for one secondin a dull style for example we will flicker the LED continually.

on each event we're starting with hardware and microcontrollers specifically, the primary mission or application we put into impact is squinting a LED as flickering a LED in gadgets is mulled over theequivalent to the whats up global in C.

At this factor of time, we can without a moment's delay transfer the exaggeration with out going further in to the programming a piece of the test. so it will transfer the sketch to the Arduino board, we need to utilize two symbols in the Arduino IDE: first is the "check or accumulate" and resulting is "add".these symbols are

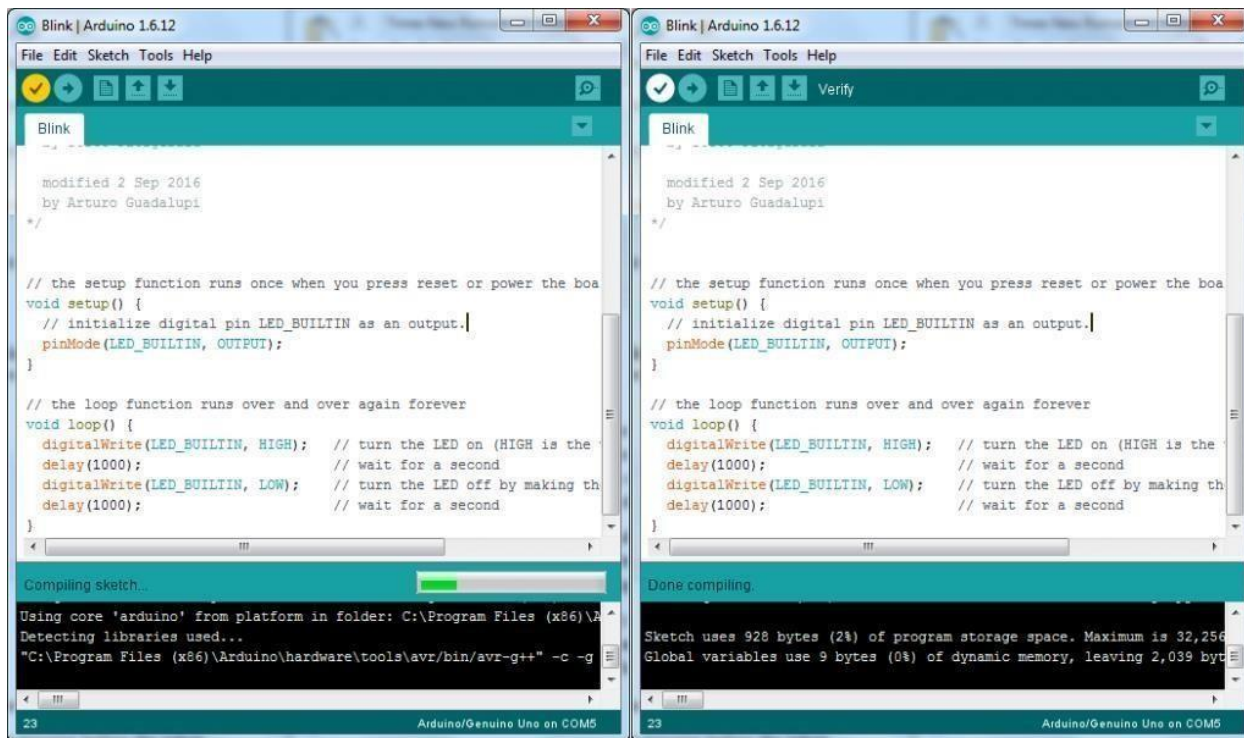
featured in the photograph under.



the first icon with a test mark is the affirm or assemble icon. the use of this icon, we will take a look at whether the written caricature is accurate or no longer in phrases of syntax and indicates the compilation mistakes,if there are any. We upload the comic strip simplest if the compilation is successful with none mistakes. rather, we can use a keyboard shortcut Ctrl + R to verify or bring together the sketch.

The element at the lowest of the IDE is called as Message window. It shows the reputation of the compilation,

error messages and the details of the errors. If we bring together the comic strip the usage of the first icon, we are able to see the status of the compilation and achieved Compilation message in the message window.



In the event that there is a slip-ups in the sketch like a missing semicolon or an unclosed section, the compilation stops by then and the message window brings up botches related to its sort and area.

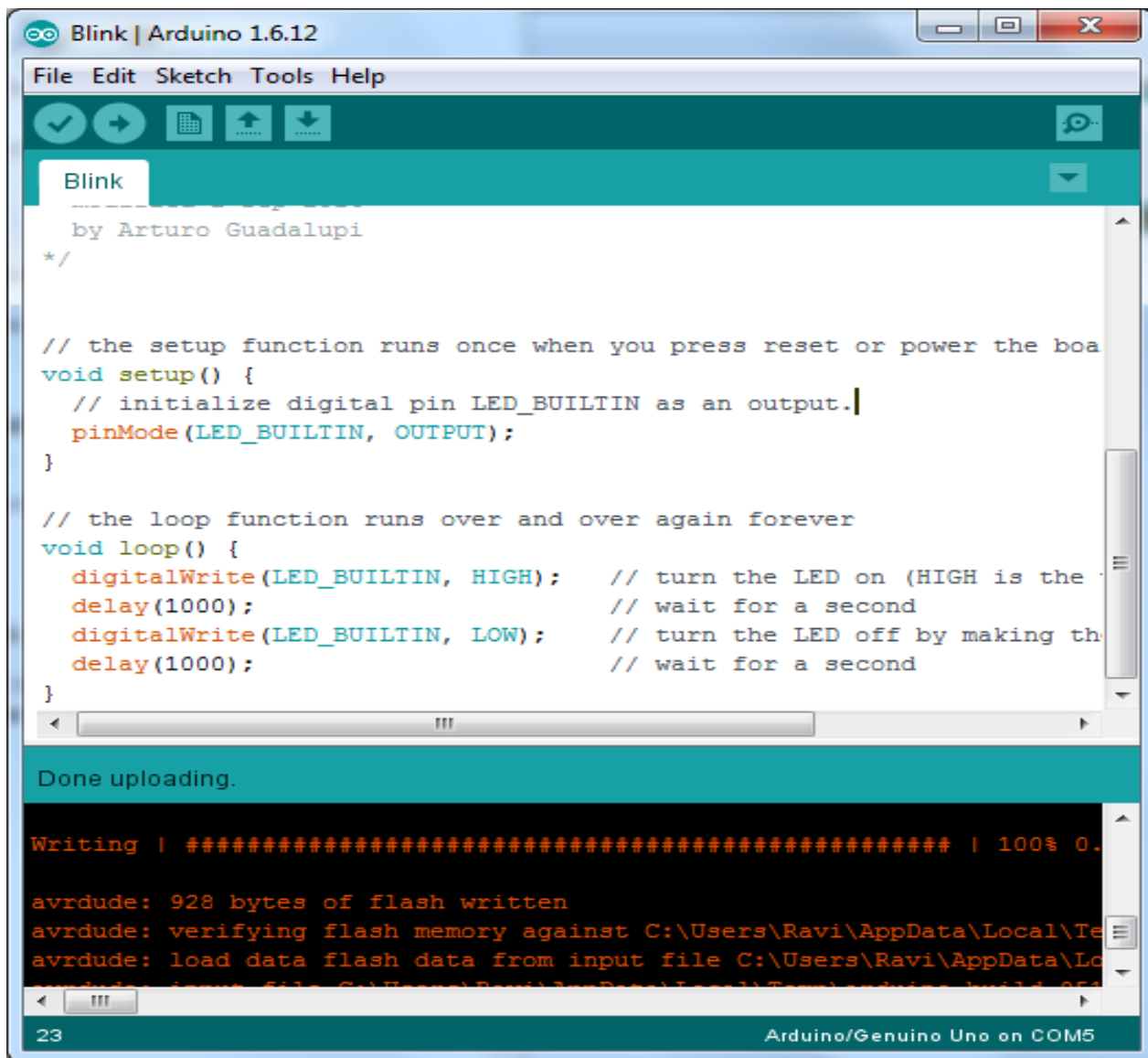
utilizing this, we can address the error.

the subsequent symbol abutting to the confirm symbol is the transfer symbol. when the accumulation of the animation is effective, at that point we will transfer the funny cartoon the utilization of this symbol. there's a console shortcut Ctrl + U to transfer the ordered cartoon. at whatever point we click at the transfer symbol, the funny cartoon is arranged prior to transferring.

As our cartoon is ordered adequately with no errors, we can hold with bringing in the personification. at the point when we click the add symbol, the sketch begin transferring and the microcontroller on the Arduino

board gets modified.

eventually of this time, the TX and RX LEDs at the Arduino UNO load up flicker as a sign that the measurements is being sent through the sequential port. when the animation is productively transferred,we will see



The screenshot shows the Arduino IDE interface. The top menu bar includes File, Edit, Sketch, Tools, and Help. Below the menu is a toolbar with icons for checking, running, and saving. The main text area displays the 'Blink' sketch by Arturo Guadalupi. The code defines a setup function to initialize the built-in LED as an output and a loop function that turns the LED on and off with 1000ms delays. The bottom status bar shows 'Done uploading.' and a progress bar. The serial monitor window at the bottom displays the upload progress, including the number of bytes written (928) and the verification status.

```
Arduino IDE - Blink | Arduino 1.6.12
File Edit Sketch Tools Help

Blink
by Arturo Guadalupi
*/

// the setup function runs once when you press reset or power the board
void setup() {
  // initialize digital pin LED_BUILTIN as an output.
  pinMode(LED_BUILTIN, OUTPUT);
}

// the loop function runs over and over again forever
void loop() {
  digitalWrite(LED_BUILTIN, HIGH); // turn the LED on (HIGH is the positive voltage)
  delay(1000);                     // wait for a second
  digitalWrite(LED_BUILTIN, LOW);  // turn the LED off by making the voltage LOW
  delay(1000);                     // wait for a second
}

Done uploading.

Writing | ##### | 100% 0.
avrdude: 928 bytes of flash written
avrdude: verifying flash memory against C:\Users\Ravi\AppData\Local\Temp\arduino_build-254\Blink.ino.hex
avrdude: load data flash data from input file C:\Users\Ravi\AppData\Local\Temp\arduino_build-254\Blink.ino.hex
avrdude: input file C:\Users\Ravi\AppData\Local\Temp\arduino_build-254\Blink.ino.hex
23 Arduino/Genuino Uno on COM5
```

The message window likewise introductions some other data like measure of glimmer memory applied by the code, time taken to transfer and so forth

as the animation is transferred adequately, the LED on the Arduino Board, that is associated with its 13th pin, will start squinting with a hole of 1 second (or as in accordance with the sketch composed).

in this instructive, we have seen an approach to transfer our first sketch to Arduino UNO board and also perceive a couple of essential elements of the Arduino IDE. inside the resulting instructive, we can look at the same sketch and comprehend the animation, its added substances and change a couple of boundaries to comprehend them better.

REUSLTANDPARAMETERS



1. VIDEO LINK :-

2. <https://photos.app.goo.gl/iQe1Ltxvg1K44>

CHAPTER5

5.1CONCLUSION

This paper gave a hand highlight restoration apparatus plan. The essential points work were to plan a gadget that could fit as a fiddle different hand measures and be both versatile and light-weight. The device was fit for accomplish total flexion/expansion movement of the four palms and thumb of the hand, based on the development of the equivalent digits of some other hand. For the model creation of the arm mount of the exoskeleton, aluminum was picked, as it's far lightweight. To get higher precision, remarks control wants to be created in future, in light of the fact that the apparatus as of now has open loop control. regardless of the way that the apparatus can perform augmentation and flexion development, it can't perform snatching/adduction development; in this manner, more prominent work wants to be done on the instrument that permits you to get whole 21 levels of opportunity (DOFs) of the hand's palms. leaving the apparatus on genuine stroke survivors, just as likewise conversations with advisors for pointers are necessary for change

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