



Corrigendum: Deep Learning-Based Haptic Guidance for Surgical Skills Transfer

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Keywords: deep learning, recurrent neural network, LSTM, haptic, force feedback, bone drilling, surgical skill transfer, COVID-19

A Corrigendum on

Deep Learning-Based Haptic Guidance for Surgical Skills Transfer

by Fekri, P., Dargahi, J., and Zadeh, M., (2021). *Front. Robot. AI* 7:586707. doi:10.3389/frobt.2020.586707

OPEN ACCESS

Edited and reviewed by:

S. Farokh Atashzar,
New York University, United States

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Specialty section:

This article was submitted to
Biomedical Robotics,
a section of the journal
Frontiers in Robotics and AI

Received: 07 April 2021

Accepted: 12 April 2021

Published: 05 May 2021

Citation:

Fekri P, Dargahi J and Zadeh M (2021)
Corrigendum: Deep Learning-Based
Haptic Guidance for Surgical
Skills Transfer.
Front. Robot. AI 8:691570.
doi: 10.3389/frobt.2021.691570

In the original article, there was a mistake in **Figure 7** as published. The figure included “Dropout”, which was not used in our reported results but can be applied to the “Dense Layers” before the output layer. Since we have not utilized “Dropout” in the reported results, the corresponding information has been removed from the caption of **Figure 7** and a correction has been made to the **Evaluation and Discussion** section, subsection **Result and Discussion, Paragraph 3:**

“Configuration 1 had 128 memory size through a one-layer LSTM network. The aim of this setup was mapping the input vector of size nine to an output vector with three elements related to the haptic force feedback prediction. Configuration 2 is the intended architecture for the DHG. This setup reached to the best result in comparison with the others. **Figure 7** demonstrates the architecture of the DHG. The prepared data (section 3.1) is fed to an LSTM, which is unrolled over $e = 20$. Every hidden state of the unrolled unit enters to another LSTM unit in layer 2. In this unit, only the output of the hidden state in time t goes to a dense layer. Since the DHG aims at estimating the forces as a regression problem, the activation function for the dense layer is a linear one.”

The corrected Figure 7 and caption appear below.

The authors apologize for this error and state that this does not change the scientific conclusions of the article in any way. The original article has been updated.

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