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(54) **ELONGATED SURGICAL MANIPULATOR WITH BODY POSITION AND DISTAL FORCE SENSING**

(75) Inventor: **Giovanni Leo**, Chene Bougeries (CH)

(73) Assignee: **Endosense SA**, Geneva (CH)

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A61M 37/00 (2006.01)

(52) **U.S. Cl.**
USPC **600/587**; 600/585; 604/95.01

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USPC 600/585, 587; 604/95.01, 95.04, 95.05, 604/164.13, 528
See application file for complete search history.

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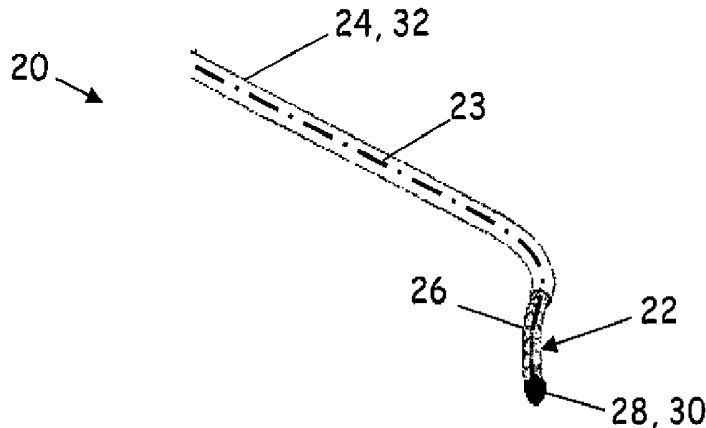
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Primary Examiner — Max Hindenburg
Assistant Examiner — Jonathan M Foreman
(74) *Attorney, Agent, or Firm* — Patterson Thunte Pedersen, P.A.

(57) **ABSTRACT**

An elongated surgical manipulator apparatus and method of operating enables determination of the shape of a flexible portion of the elongated surgical manipulator and/or the location of an arbitrary point thereon, as well as a measure of a contact force exerted on a distal portion of the manipulator. A plurality of fiber optics are operatively coupled with the manipulator, each of the fiber optics including a plurality of fiber Bragg gratings for determination of the shape and/or position. Each of the fiber optics further includes a fiber optic strain gauge such as a Bragg grating or a Fabry-Perot resonator at a distal portion of the elongated surgical manipulator that is isolated from the strain associated with the bending of the manipulator. The fiber optic strain gauges at the distal portion may thus be used to detect a force vector (magnitude and direction) imposed on the distal portion.

9 Claims, 8 Drawing Sheets



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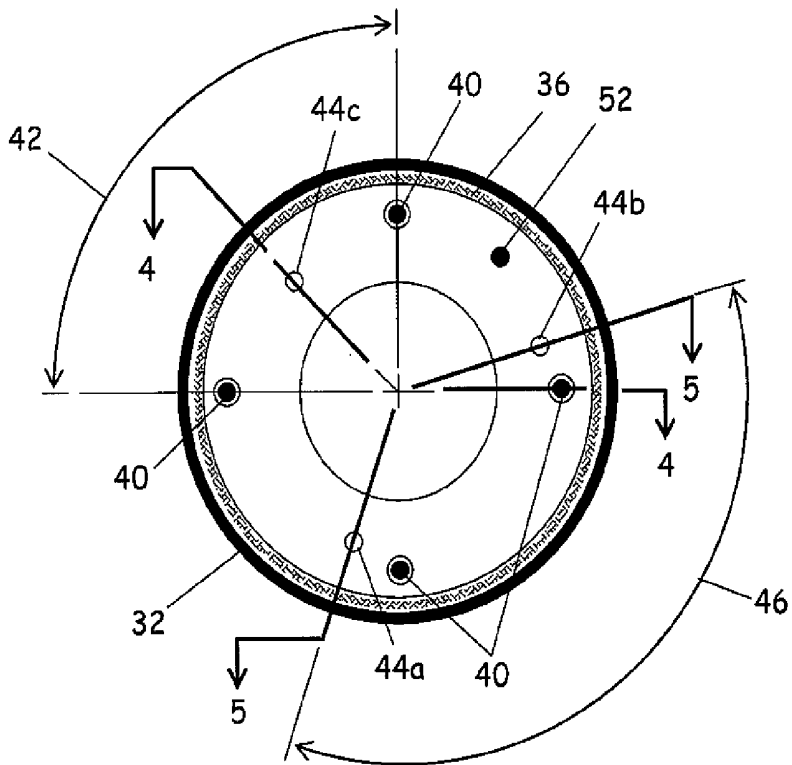
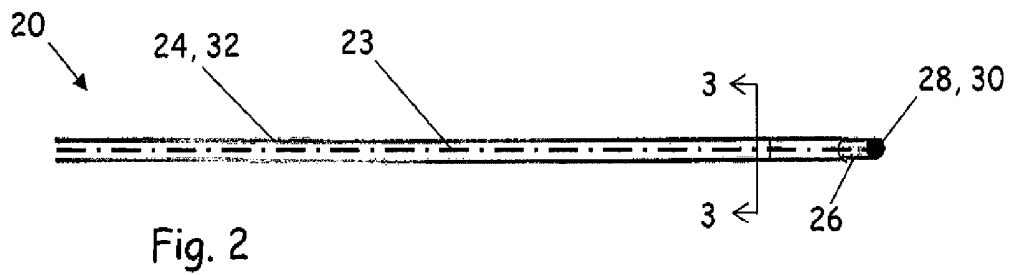
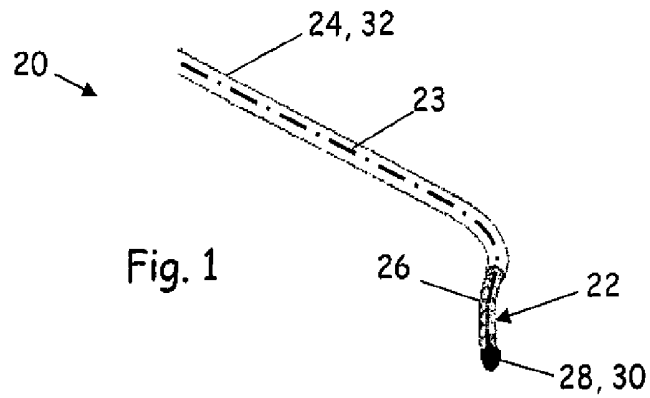
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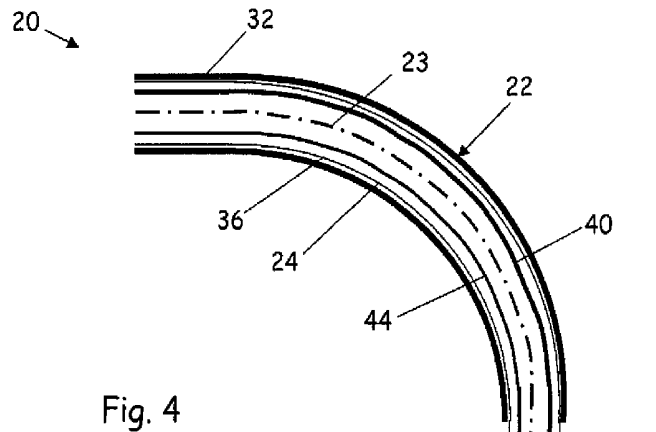


Fig. 4

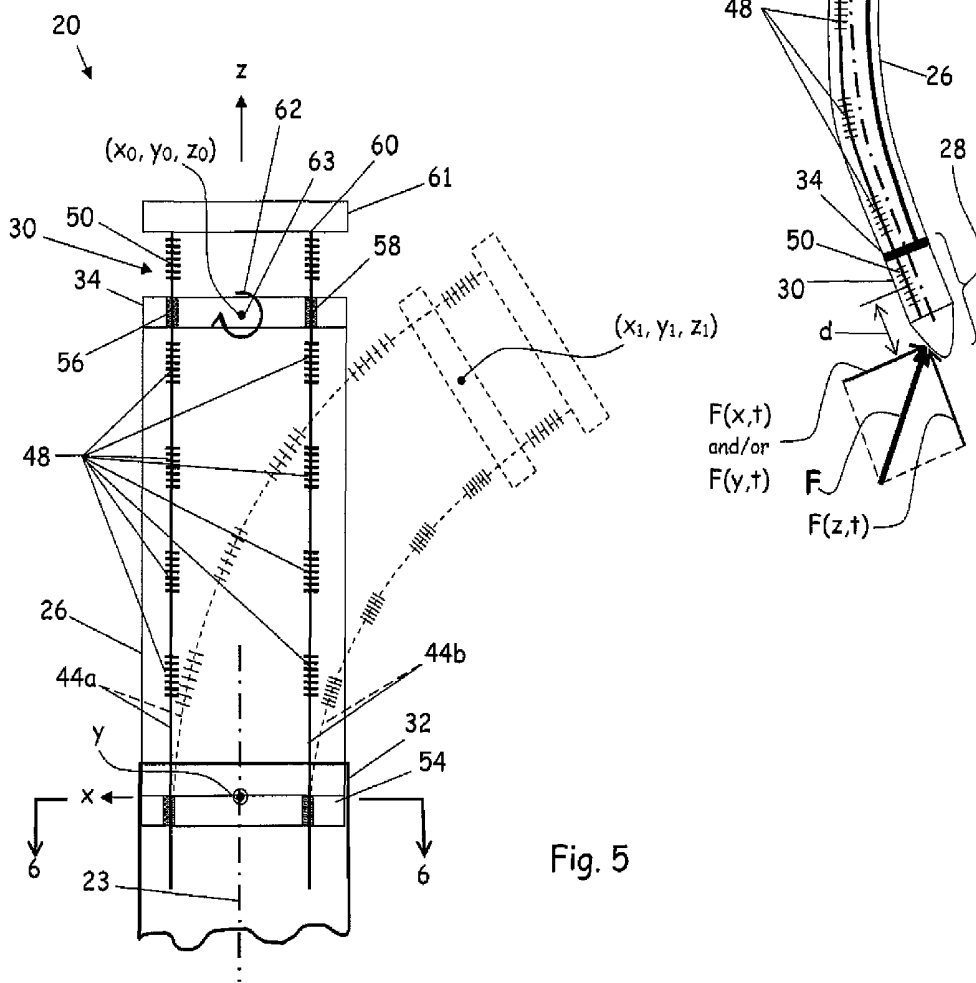


Fig. 5

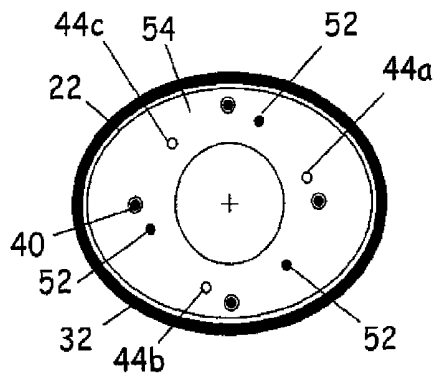


Fig. 6A

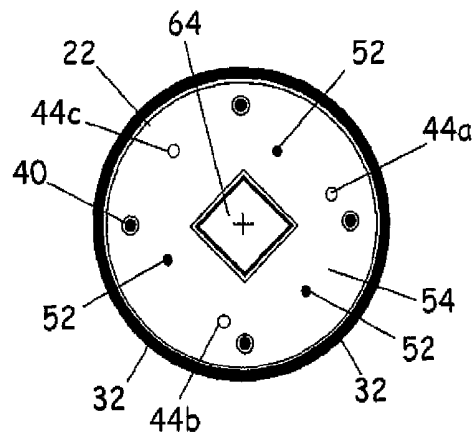


Fig. 6B

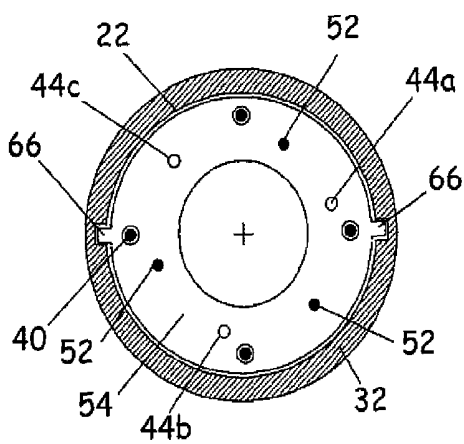


Fig. 6C

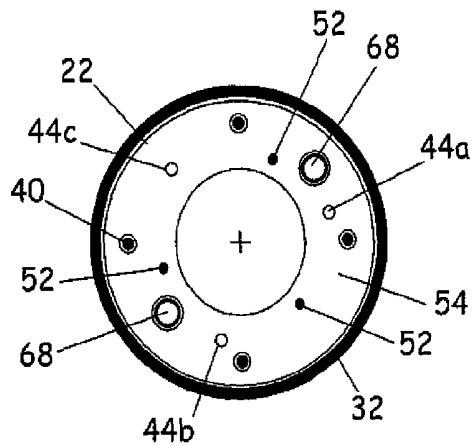


Fig. 6D

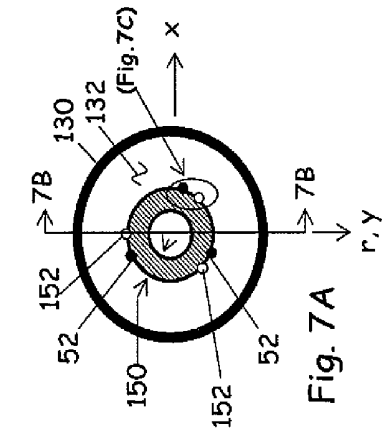


Fig. 7A

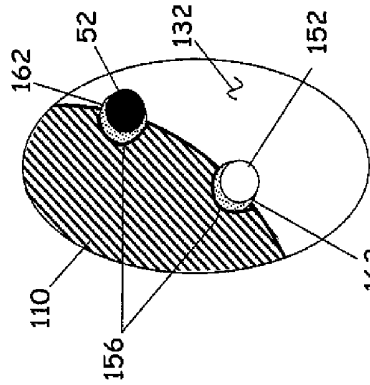


Fig. 7C

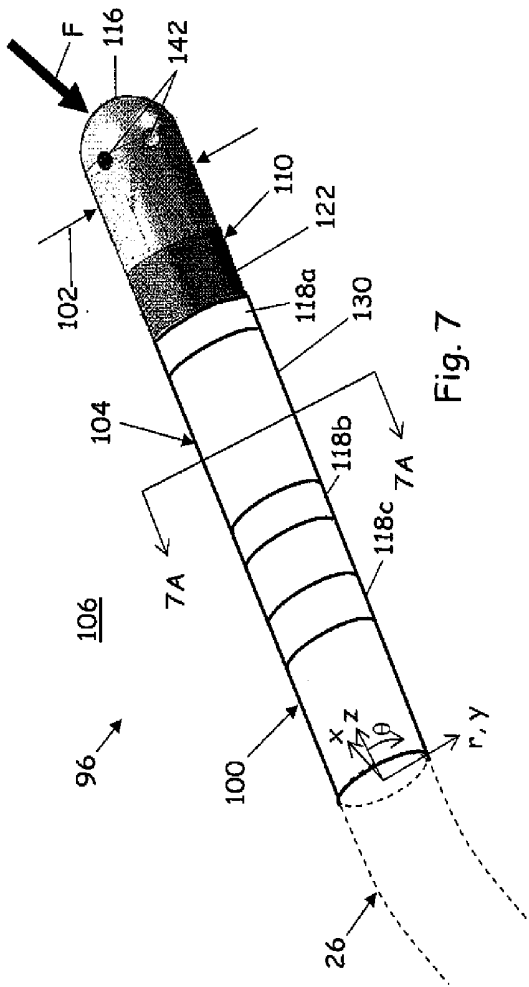


Fig. 7

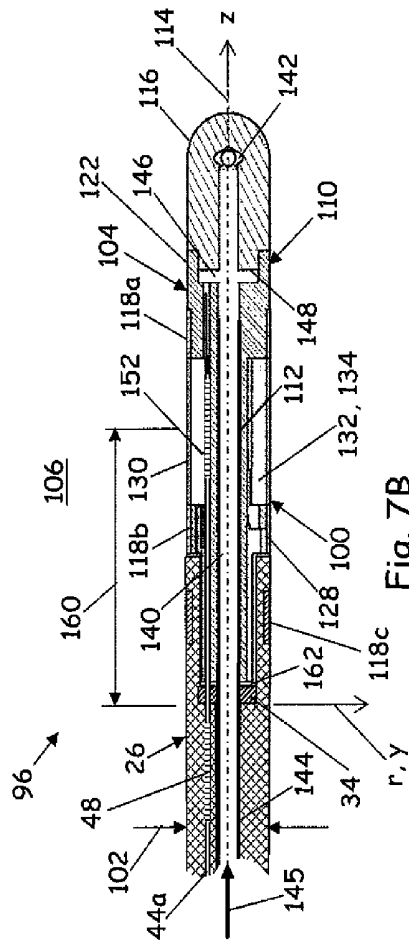


Fig. 7B

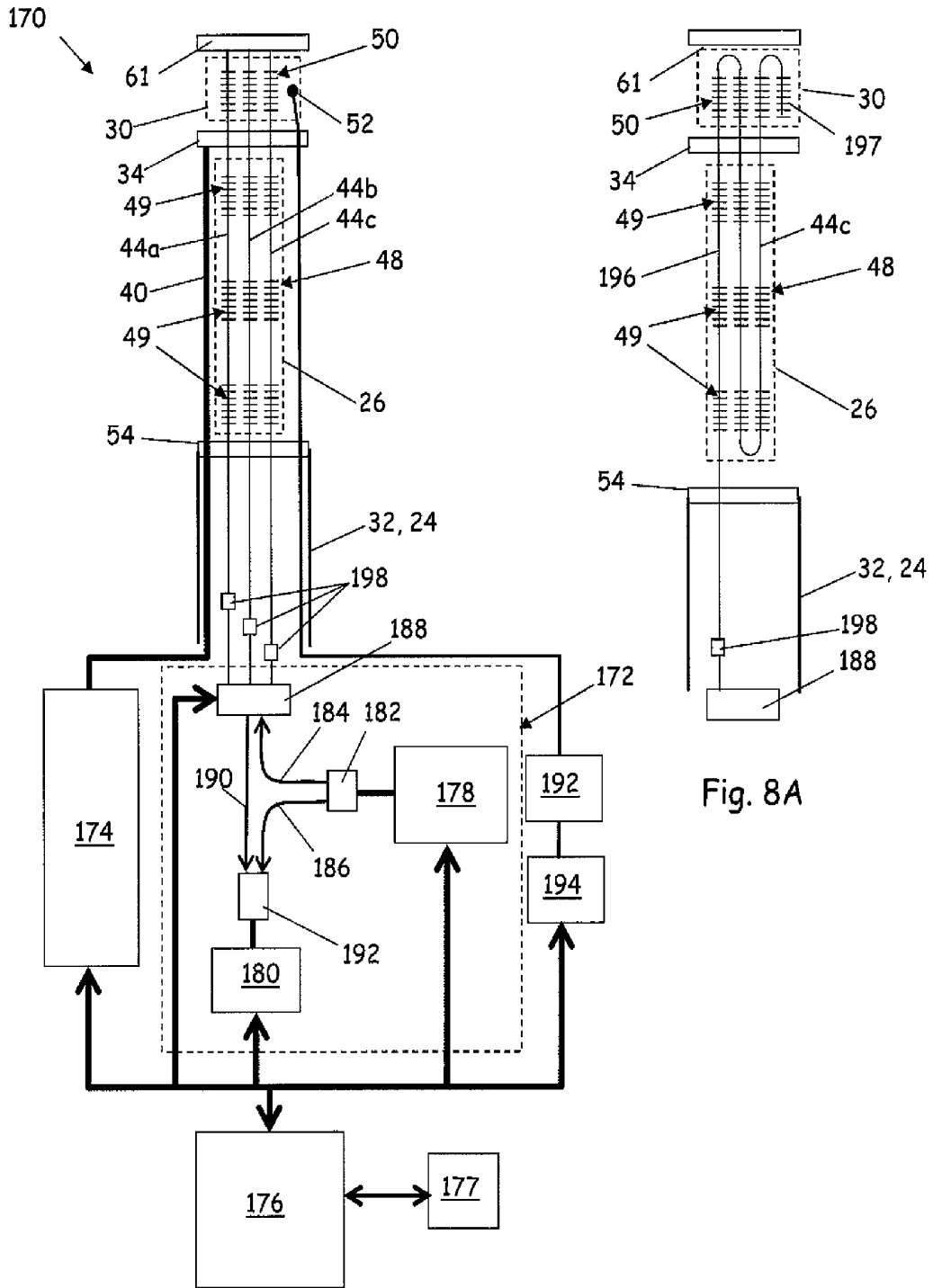
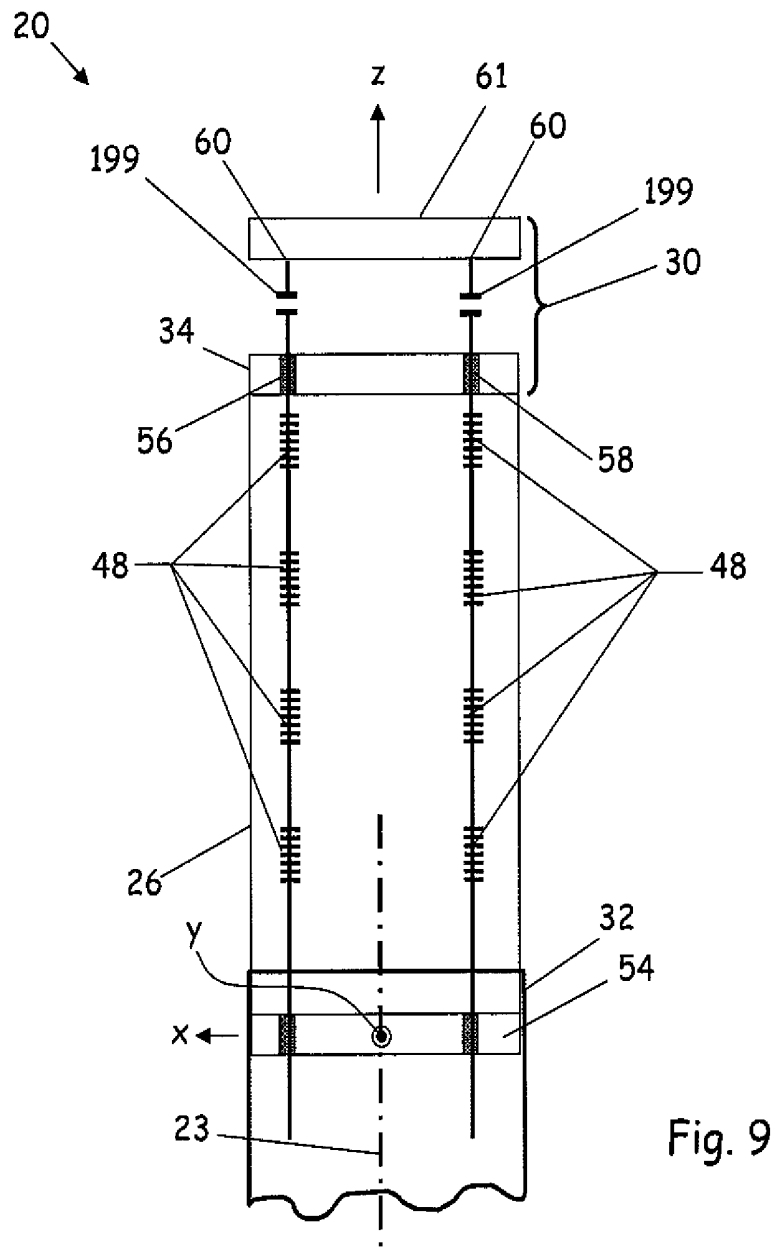


Fig. 8A

Fig. 8



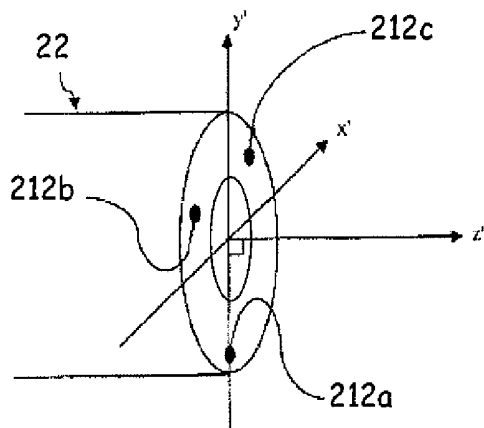


Fig. 10A

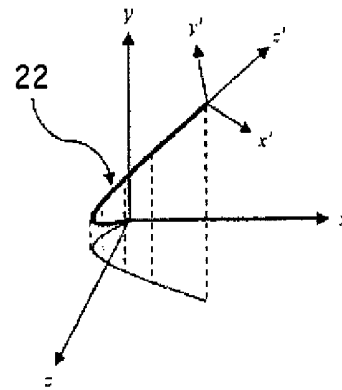


Fig. 10B

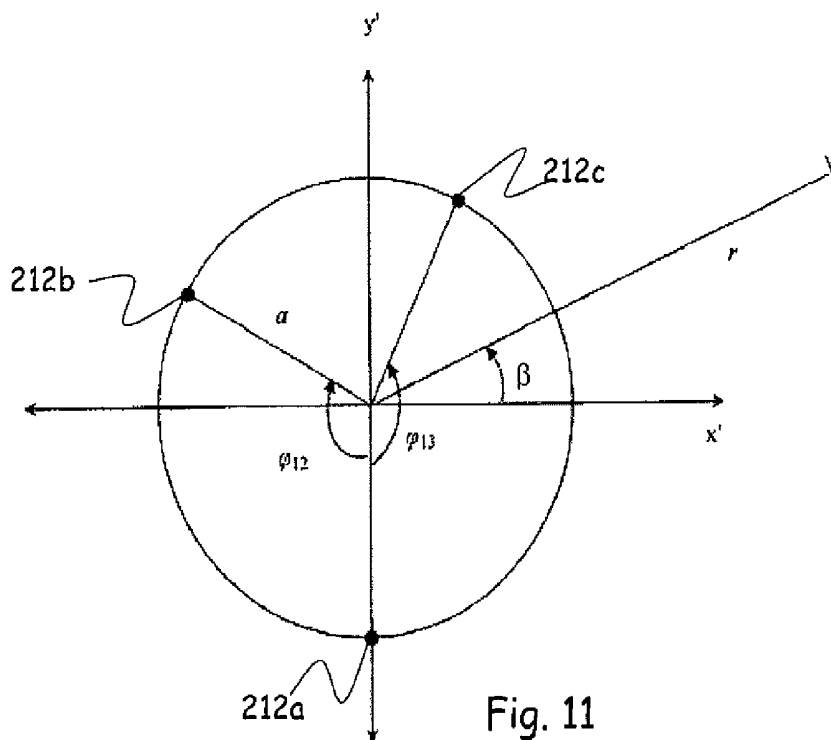


Fig. 11

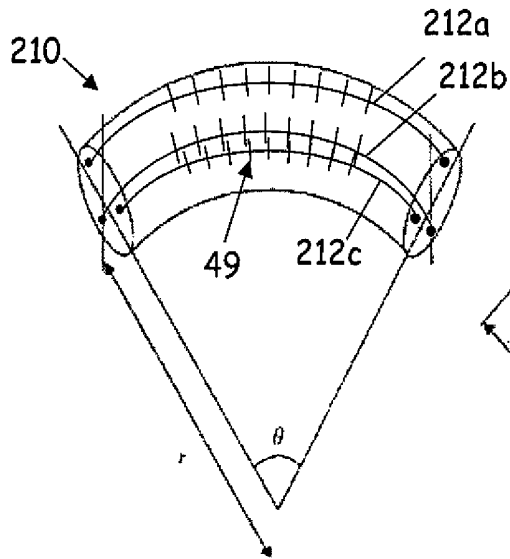


Fig. 12A

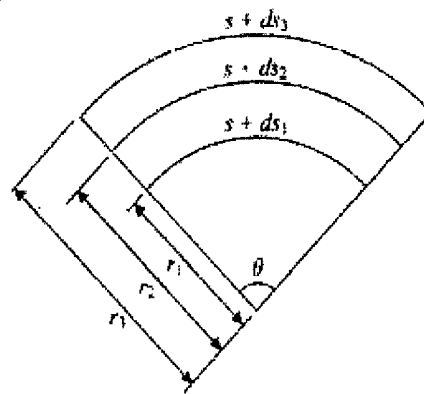


Fig. 12B

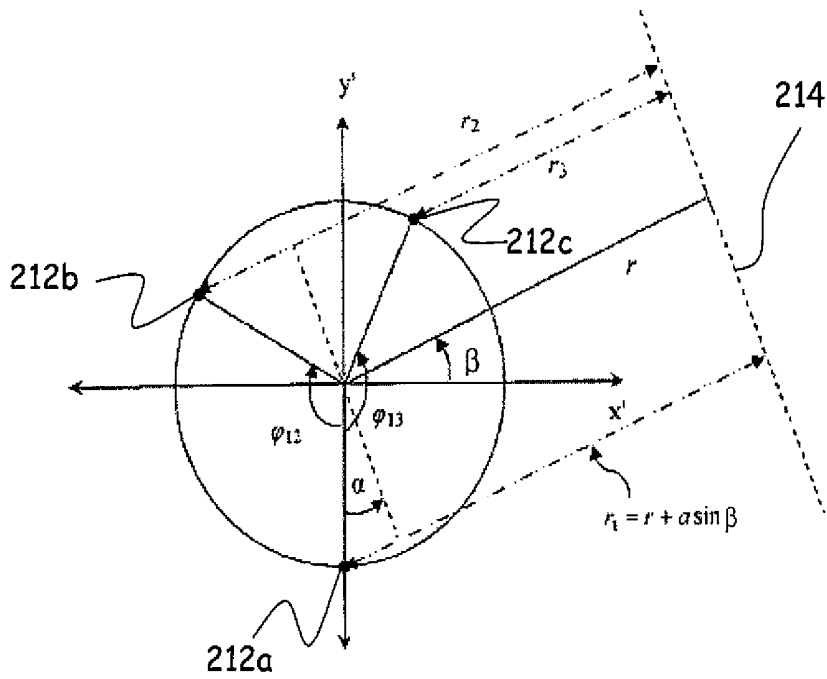


Fig. 13

ELONGATED SURGICAL MANIPULATOR WITH BODY POSITION AND DISTAL FORCE SENSING

RELATED APPLICATION

The present application claims priority to U.S. Provisional Application No. 60/931,762 filed May 25, 2007, which is incorporated herein in its entirety by reference.

FIELD OF THE INVENTION

The disclosed invention relates generally to sensing devices capable of resolving the position of an elongated surgical manipulator as well as the magnitude and direction of a force vector externally imposed on a distal portion of the surgical manipulator. More specifically, the invention relates to a manipulator with elongated body shape resolution and a force sensing distal tip to aid in the positioning of catheters used in humans or animals, or for serving as feedback elements in robotic surgical systems.

BACKGROUND OF THE INVENTION

The use of optical fiber strain sensors to detect the reactionary force on the end effector of a catheter is known. U.S. Patent Application Publication No. 2007/0060847 to Leo et al. (Leo I), assigned to the assignee of the present application, discloses an apparatus and method using fiber Bragg gratings coupled to a deformable body for inferring the magnitude and direction of a reaction force imparted on the distal portion of an end effector. U.S. patent application Ser. No. 11/753,429 to Leo et al. (Leo II), also assigned to the assignee of the present application, discloses an apparatus and method using Fabry-Perot resonators operatively coupled to a fiber optic to infer the magnitude and direction of reaction forces imparted on the distal portion of an end effector. While these devices have advanced the art in terms of resolving the forces applied in touch sensitive operations such as ablation procedures, they lack an integrated way of determining the position or location of the catheter during the procedures. Instead, the position of the catheter and/or end effector within a patient must be determined by an alternative approaches such as fluoroscopy or fMRI.

Position sensing and shape resolution using multiple arrays of fiber Bragg gratings is also known for elongated catheter bodies without an end effector. U.S. Patent Application Publication No. 2007/0065077 to Childers et al. (Childers) and U.S. Patent Application Publication No. 2007/0265503 to Schlesinger, et al. (Schlesinger) disclose the use of fiber Bragg gratings operatively coupled to an elongate flexible body to sense the local strains of the body at a multitude of points, and a method for inferring the shape of the body and a position of the distal portion of the elongated catheter body based on the strain imposed on the fiber Bragg gratings.

A system that enables accurate determination of touching forces on a distal portion in combination with simultaneous accurate position sensing of an elongated surgical manipulator would be welcome.

SUMMARY OF THE INVENTION

Various embodiments of the disclosed invention provide effective apparatuses and procedures for resolving shape, position and force sensing of automated or manually controlled elongated surgical manipulators. Certain embodiments include the dual function of position indication of an

end effector of the elongated surgical manipulator and the magnitude and direction of a reaction force exerted thereon.

Certain embodiments include a surgical manipulator arm or catheter body having an elongate flexible body that includes one or more fiber optics, each fiber optic being equipped with a number of fiber Bragg gratings. The elongate flexible body may include a flexing portion and a distal portion. In some embodiments, the flexing portion includes a plurality of fiber Bragg gratings and is configured for flexing with a steering mechanism, the operation of which does not flex the distal portion. The distal portion may include fiber optic sensors, such as fiber Bragg gratings or Fabry-Perot resonators, that are isolated from the flexing strain experienced by the flexing portion, and thus are suited for detecting deflection due to reaction forces imposed on the distal portion.

Embodiments of the present invention overcome the problems which would otherwise preclude combining the position sensing teaching of Childers and Schlesinger with the force sensing arrangements disclosed by Leo I or Leo II. Neither Childers nor Schlesinger have an end effector or can provide for an irrigation passage extending through the flexible elongate body. In particular, Schlesinger teaches a catheter having a soft tapered distal tip that is even more pliable than the flexible portion of the manipulator. (See U.S. Patent Application Publication No. 2006/0100610, which Schlesinger incorporates by reference in its entirety.) Such a tip is incompatible with the requirements of a force sensing assembly using fiber optics at the distal portion of an elongated surgical manipulator because the tip will generally flex under its own weight and cause the optical fiber strain sensors to undergo an orientation, non-force related strain. Soft pliable tips are also incompatible with ablation and/or irrigation end effectors.

In various embodiments of the present invention, an electromagnetic source, such as a tunable laser, may be used to interrogate each of the fiber optics. The reflected wavelengths from fiber Bragg gratings corresponding to the flexing portion provides knowledge of the strain of each, from which the shape or geometric configuration of at least a portion of the elongate flexible body may be inferred. The inferred shape may also provide knowledge of the position of the distal extremity of the elongate flexible body.

In another embodiment of the invention, the elongate body may be a catheter having an end effector such as an ablation catheter. The end effector may have a rigid or semi-rigid section that enables a stable reference, for example where the catheter goes through the septum in a left atrium intervention from the femoral vein.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 is a partial perspective view of a manipulator arm in an embodiment of the invention;

FIG. 2 is a side elevation view of the manipulator arm of FIG. 1;

FIG. 3 is an enlarged sectional view of the manipulator arm of FIG. 2;

FIG. 4 is a sectional view of the manipulator arm of FIG. 3;

FIG. 5 is a partial and enlarged schematic of a section of the manipulator arm of FIG. 3 in operation;

FIGS. 6A through 6D are enlarged, exemplary cross-sections of the base within a rigid tube member for various embodiments of the invention;

FIG. 7 is a perspective view of an end effector having a force sensor assembly and an ablation head in an embodiment of the invention;

FIGS. 7A and 7B are sectional views of the force sensing assembly of FIG. 7;

FIG. 7C is an enlarged partial view of the sectional view of FIG. 7A;

FIG. 8 is a schematic of a force manipulator system in an embodiment of the invention;

FIG. 8A is a partial schematic of a force manipulator system in an embodiment of the invention;

FIG. 9 is a partial and enlarged schematic of a manipulator arm in an embodiment of the invention;

FIGS. 10A and 10B depict a sensor frame coordinate system in an embodiment of the invention;

FIG. 11 depicts a bend parameter schematic in an embodiment of the invention;

FIGS. 12A and 12B depict a bend geometry of an instrumented flexible section in an embodiment of the invention; and

FIG. 13 depicts a cross-section of an instrumented flexible section in an embodiment of the invention.

DETAILED DESCRIPTION OF THE DRAWINGS

Referring to FIGS. 1 and 2, a manipulator arm 20 comprising an elongate flexible instrument body 22 is depicted in an embodiment of the invention. The elongate flexible body 22 defines a longitudinal axis 23 that conforms to the shape of and runs the length of the elongate flexible body 22. The elongate flexible body 22 includes a proximal portion 24 and a flexing portion 26. The manipulator arm 20 may further include an end effector 28 that defines a distal portion 30 of the manipulator arm 20.

The proximal portion 24 may be supported by a rigid member 32. In the depicted embodiment, the rigid member 32 is a tubular member that serves as a cladding for the elongate flexible body 22 over the length of the proximal portion 24. The distal portion 30 may include a yoke portion 34 at the interface with the flexing portion 26. The proximal portion 24 may be permanently attached to the rigid member 32, or may be configured to move along the longitudinal axis 23 relative to the rigid member 32. In still other embodiments, the flexing portion 26 is anchored directly to a base without use of a rigid member (not depicted).

Referring to FIGS. 3 through 5, the manipulator arm 20 is depicted as having a plurality of push-pull cables 40 that run the length of the elongate flexible body 22 in an embodiment of the invention. In this embodiment, there are four push-pull cables 40 in uniform rotational displacement 42 about the longitudinal axis 23 and operatively coupled with the yoke portion 34. The FIG. 3 embodiment also includes a trio of fiber optics 44a, 44b and 44c (aka optical fiber cores) also in uniform rotational displacement 46.

In one embodiment, each of the fiber optics 44a, 44b, 44c includes a plurality of flexing portion fiber Bragg gratings 48 for determining the shape of the flexing portion 26, and/or the location of the distal portion 30. The flexing portion fiber Bragg gratings 48 may be positioned on the respective fiber optic 44a, 44b or 44c such that the fiber Bragg gratings 48 are disposed within the flexing portion 26.

The fiber optics 44a, 44b, 44c may each have the same axial spacing between the flexing portion fiber Bragg gratings 48. A typical and non-limiting axial spacing is on the order of 1- to 2-cm. The fiber optics 44a, 44b and 44c may also be aligned so that the flexing portion fiber Bragg gratings 48 are grouped in "sensor triplets" 49 (i.e. three sensors located at substantially the same axial location along the z-axis) at various axial locations along the z-axis of the flexing portion 26. That is, for every flexing portion fiber Bragg grating 48 on fiber optic

44a, there are also corresponding flexing portion fiber Bragg gratings 48 on fiber optics 44b and 44c centered at substantially the same axial location along the flexing portion 26. The sensor triplets 49 are best depicted in FIG. 8.

At least one of the fiber optics 44a, 44b and/or 44c also extends through or past the yoke portion 34 and includes a distal fiber Bragg grating 50, disposed in and operatively coupled to the distal portion 30. The distal fiber Bragg grating(s) 50 may be utilized to determine a force component or components exerted on the distal portion 30 (e.g. such as described in the discussion attendant FIG. 7).

It is understood that the force component "exerted on" the distal portion 30 may be the result of an object moving into contact with a substantially stationary distal portion 30, or the result of reaction forces caused by moving the distal portion 30 into contact with a substantially stationary member, or a combination thereof.

One or more temperature sensors 52 (FIG. 3) may also extend through the elongate flexible body 22 and be operatively coupled proximate the distal fiber Bragg gratings 50.

In FIG. 5, two of the fiber optics 44a and 44b of the manipulator arm 20 are schematically depicted in an embodiment of the invention and to illustrate the operation of the invention generally. The fiber optics 44a and 44b are each depicted as having the flexing portion and the distal fiber Bragg gratings 48, 50. In this embodiment, the fiber optics 44a and 44b are connected to a base 54 operatively coupled to the rigid member 32 at the interface between the proximal portion 24 and the flexing portion 26. The center of this interface may also be utilized to define the origin of an x-y-z coordinate system, as depicted in FIG. 5.

The fiber optics 44a and 44b may extend through the yoke portion 34 and may also be securely connected to the yoke portion 34 at anchor locations 56. Each of the anchor locations 56 may be affected by a potting- or adhesive-filled orifice 58 that bonds the respective fiber optic 44a and 44b to the yoke 34. Each of the fiber optics 44a and 44b includes a distal extremity 60 that may be operatively coupled to a force transfer member 61. The elongate flexible body 22, or portions thereof, may include or be contained within a braided sleeve 36.

In operation, the push-pull cables 40 may cooperate with each other to impart a torsion or moment 64 about the yoke portion 34 that causes the flexing portion 26 to flex and the yoke portion 34 to move from a default or "at rest" position (x_0, y_0, z_0) to an activated position (x_1, y_1, z_1). In the FIG. 5 depiction, the moment 62 is about a moment axis 63 that is perpendicular to the plane containing the two fiber optics 44a and 44b, which causes the yoke portion 34 to exert a tension load on fiber optic 44a and a compression load on fiber optic 44b. The tension/compression loads cause a change in the spacing of the respective flexing portion fiber Bragg gratings 48, which in turn shifts the wavelength of the light waves reflected by the fiber Bragg gratings 48.

Inference of position may be based on the differential strain between individual flexing portion fiber Bragg gratings 48 of a given sensor triplet 49. (See Eqn. (6) and attendant discussion below.) It was previously thought that the dependence on differential strains made the shape determination insensitive to temperature changes because the thermal expansion/contraction of one strain sensor would be matched by the thermal expansion/contraction of the other strain sensors of the sensor triplet 49. This is true only where the temperature changes of flexing portion 26 are tangentially uniform at the location of the sensor triplet 49. In some applications, such as catheter systems that generate high thermal energy (e.g. ablation catheters), thermal gradients in the surroundings may cause one

portion or side of the flexing portion **26** to be at a different temperature than the another portion or side, thereby introducing a temperature gradient between individual flexing portion fiber Bragg gratings **48** of the same sensor triplet **49**.

To remedy against tangential thermal gradients, the flexing portion fiber Bragg gratings **48** may be coupled closely to the irrigation source passage **144**, as depicted in FIG. 7B. This way, the temperature of the flexing portion fiber Bragg gratings **48** may be dominated by the flow of the irrigation fluid **145** and also isolated from the operating environment **106** by a greater thickness of the flexible material that comprises the flexing portion **26**.

The fiber optics **44a** and **44b** may be coupled with the yoke portion **34**, and the portion of the fiber optics **44a** and **44b** in the distal portion **30** (i.e. between the potting-filled orifices **58** and the force transfer member **61**) are isolated from compression and tension loads experienced in the flexing portion **26**. By this arrangement, the distal fiber Bragg gratings **50** included in the distal portion **30** theoretically do not experience a strain due to the flexing of the flexing portion **26**. In practice, the forces exerted on the yoke portion **34** may cause some flexure of the end effector **28** relative to a neutral orientation, which may translate to a detectable strain on the distal fiber Bragg gratings **50**. These effects are generally repeatable and thus can be calibrated and compensated as a function of the position (e.g. x-y-z location) relative to the distal portion **30**.

The temperature sensor **52** may be positioned proximate the distal fiber Bragg gratings **50** to estimate the temperature of the distal fiber Bragg gratings **50**.

The number of components of the force vector that can be resolved is limited by the number of distal fiber Bragg gratings **50**. That is, a single distal fiber Bragg grating **50** will resolve only a strain that is parallel to its length, and at best can only infer the local axial force component. A pair of distal fiber Bragg gratings **50** may define an axial and a tangential force component, assuming a neutral axis between the two distal fiber Bragg gratings **50**. And a trio of distal fiber Bragg gratings **50** will resolve an axial component (i.e. a z-axis component) and orthogonal tangential force components (i.e. x- and y-axis components), which further enables determination of the three-dimensional orientation of the force vector.

The braided sleeve **36** may provide a degree of stiffness to the flexing portion **26** that is desirable for certain applications. For embodiments where the elongate flexible body **22** moves relative to the rigid member **32**, the braided sleeve **36** may also provide abrasion resistance.

The tension/compression of the flexing portion fiber Bragg gratings **48** for a given bend may vary depending on the orientation of the respective fiber optic **44a**, **44b** or **44c** relative to the plane of bending. For example, for the bending in the plane that contains both fiber optic **44a** and **44b** (such as depicted in FIG. 5), fiber optic **44c** is located equidistant between the fiber optics **44a** and **44b** and may conform to a neutral axis or plane such that the flexing portion fiber Bragg gratings positioned thereon experience little or negligible strain.

The use of three or more push-pull cables enables an operator to control the position of the yoke portion **34** in three dimensions. The invention may be configured with just two push-pull cables, enabling control of a lateral movement or with a pull-wire that cooperates with a plane and a leaf spring to return the catheter the straight position (not depicted). The number and arrangement of push-pull cables **40** may be configured to provide bending in a plurality of planes. Accordingly, the flexing portion fiber Bragg gratings **48** on any one of the fiber optics **44** may experience varying degrees of tension,

compression. In some configurations, some of the flexing portion fiber Bragg gratings **48** on a given fiber optic **44** may experience a tension while others on the same fiber optic **44** may experience a compression.

Referring to FIGS. 6A through 6D, the base **54** may also be configured to slide along the rigid member **32** in other embodiments of the invention. For example, where a rigid tube is utilized as the rigid member **32**, the base **54** may be dimensioned for sliding engagement with the interior of the tube. The tube may have a non-circular cross-section, such as the oval shape depicted in FIG. 6A, or be configured to cooperate with a non-circular center guide **64**, such as the square cross-sectional rod depicted in FIG. 6B. The cross-section of the base **54** may cooperate with a track structure **66**, such as a tongue and groove structure formed with the rigid member **32** (FIG. 6C) or a plurality of guide rods **68** located within the proximal portion **24**. While the rigid members depicted in FIGS. 6A through 6D comprise hollow tubular structures, it is understood that other support structures such as rods, cages or brackets may be utilized for the rigid member **32**.

Functionally, the various cross-sections depicted in FIGS. 6A through 6D limit the rotation or twisting of the base **54** relative to the rigid member **32** while enabling movement of the base **54** along the longitudinal axis **23**.

Referring to FIGS. 7 and 7A through 7C, an end effector **96** including a strain sensing assembly **100** is depicted in an embodiment of the invention. The end effector **96** may be utilized as the end effector **28** of FIG. 4. The temperature compensated strain sensing assembly **100** may have an overall diameter **102** and is depicted as being immersed in an operating environment **106**. The temperature compensated strain sensing assembly **100** includes a deformable body **110** having an outer surface **112** and defining a central axis **114**. In the depicted embodiment, the temperature compensated strain sensing assembly **100** comprises an ablation head **116** operatively coupled to the deformable body **110**, and external sleeve electrodes **118a**, **118b** and **118c**. An external force vector **F** is depicted as being applied to the ablation head **116**. Dual coordinate systems (i.e. Cartesian x-y-z and cylindrical r-O-z) are depicted at the base of the deformable body **110**.

The deformable body **110** may include a collar portion **122**, a neck portion **124** having a neck radius **126**, a radial standoff structure **128**, and an outer sleeve **130** that surrounds the neck portion **124**. The outer sleeve **130** may bridge between the radial standoff structure **128** and the collar portion **122** and cooperate with the neck portion **124** to define an annular gap **132**. The annular gap **132** may include a thermal insulator **134**.

An irrigation passage **140** may be defined as passing through the deformable body **110** and the ablation head **116**, and may terminate at irrigation outlets **142** formed in the ablation head **116**. An irrigation source passage **144** may be operatively coupled with the irrigation passage **140** for sourcing the irrigation passage **140** with irrigation fluid **145**. An axial gap **146** may be defined between the deformable body **110** and a base surface **148** of the ablation head **116**.

In one embodiment, a representative wall thickness **150** is approximately 200- to 300-micrometers; however, this wall thickness may not be representative or limiting for all embodiments.

A plurality of optical fiber strain sensors **152** may be operatively coupled to the deformable body **110**. The one more temperature sensors **52** may also be operatively coupled to the deformable body **110**. In one embodiment (depicted), the number of temperature sensors **52** is equal to the number of distal fiber Bragg gratings **50**, one temperature sensor **52** for

a corresponding distal fiber Bragg grating **50**, with the sensitive portion of temperature sensor **52** being mounted in close proximity to the corresponding distal fiber Bragg grating **50**. Channels **156** may be defined on the outer surface **112** of the deformable body **110** and the sensors **152**, **52** coupled thereto. The sensitive portions of the optical fiber strain sensors **152** and temperature sensor(s) **52** may be substantially centered at the same axial location **160** relative to a proximal end **162** of the deformable body **110**.

Generally, the deformable body **110** may comprise a polymeric material such as liquid crystal polymer (LCP) or polyetheretherketone (PEEK). Generally, the deformable body **110** is stiffer than the flexing portion **26** of the catheter so that deformable body **110** does not flex under its own weight and cause the optical fiber strain sensors **152** to undergo an orientation, non-force related strain. The channels **156** may aid in the precise location of the sensitive portions of the sensors **50**, **52**. Each optical fiber strain sensor **152** may comprise a fiber Bragg grating sensor (e.g. distal fiber Bragg grating **50**) or a Fabry-Perot sensor.

Operative coupling of the optical fiber strain sensor **152** and/or the temperature sensor(s) **52** may be accomplished in one embodiment using a glue **162**. The glue **162** may be placed in the channels **156** or on the optical fiber strain sensors **152** and the strain sensors **152** placed in the channels **156**. Excess glue may be removed after placement. Some glues may enable placement of the optical fiber strain sensors **152** in the channels **156** followed by a coating or dabbing of glue on the optical fiber strain sensors **152** to secure it to the channels **156**.

Another bonding technique may involve the use of a solvent designed to cause the material of the deformable body **110** to melt or flow while not affecting the material of the strain sensors **152**. The solvent may be applied to an area or zone of the deformable body **110** that encompasses at least a portion of the channels **156** where the strain sensors **152** are to be mounted, and the optical fiber strain sensors **152** placed therein. Alternatively, the optical fiber strain sensors **152** may be temporarily held in place in the channels **156** of the deformable body **110** and the solvent applied as a coating over both. The flowing of the material in and around the channels **156** can cause a bond between the deformable body **110** and the optical fiber strain sensors **152**. The solvent may be removed by a process such as washing or evaporation to arrest the melting process.

While the mounting and bonding techniques above are directed to an embodiment that includes channels **156**, it is recognized that the same procedures may be utilized in the absence of channels **156**.

Dimensionally, representative and non-limiting ranges for the various parameters include the overall diameter **102** of approximately 2.3-mm, the irrigation passage **140** of approximately 0.4- to 0.8-mm diameter, and the representative wall thickness **150** on the order of 200- to 300-micrometers.

Functionally, the reduced neck radius **126** of the neck portion **124** and/or the decreased diameter of the irrigation passage **140** relative to certain existing configurations provides several advantages. For a given flow rate of irrigation fluid **145**, the smaller diameter irrigation passage **140** increases the Reynolds number of the fluid flow, which can increase the convection heat transfer coefficient between the irrigation fluid **145** and the boundary of the irrigation passage **140**, thereby enhancing the overall heat transfer between the irrigation fluid **145** and the optical fiber strain sensors **152**. The reduced radius **126** may also provide a reduced cross-section of material, thereby reducing the thermal conductance through the neck portion **124** in the axial direction **Z** and the

thermal coupling between the ablation head **116** and the optical fiber strain sensors **152**. The wall thickness **150** of the neck portion **124** can also be tailored for a desired sensitivity (displacement) of the temperature compensated strain sensing assembly **100** in response to the force vector **F**. The reduced neck radius **126** of the neck portion **124** may also provide an increased thickness of the annular gap **132** relative to existing designs, thereby enhancing the thermal isolation between the operating environment **106** and the optical fiber strain sensors **152**.

The channels **156**, when present, may further decrease the thermal conduction path between the irrigation fluid **145** and the optical fiber strain sensors **152**.

The axial gap **146**, being flooded with irrigation fluid **145**, may actively cool the base surface **148** of the ablation head **116** and mitigate against axial conduction of heat between the base surface **148** and the deformable body **110**.

By these various thermal management aspects, various embodiments of the invention may cause the optical fiber strain sensors **152** to be dominated by the temperature of the irrigation fluid **145**, with the influence of the ablation head **116** and the surroundings being secondary. An advantage of having the irrigation fluid **145** dominate the thermal state of the optical fiber strain sensors **152** is that the temperature of the irrigation fluid **145**, as well as the convective coupling between the irrigation fluid **145** and the irrigation passage **140**, tends to be more stable than the temperature of the ablation head **116** and the temperature and convective coupling between the operating environment **106** and the outer sleeve **130** during operation.

In operation, the temperature sensor(s) **52** may be utilized to compensate for the thermal expansion/contraction of the optical fiber strain sensors **152** relative to the calibration or nulling state. For configurations where the irrigation fluid **145** dominates the temperature of the neck portion **124**, the temperature profile of the neck portion **124** may be substantially uniform or at least be substantially linear with respect to the axial coordinate **Z**, with no substantial variation tangentially in the temperature of the deformable body **110** at a given axial location (e.g. **160**). In such conditions, a single temperature sensor **52** may be sufficient to accomplish the temperature compensation, particularly if the optical fiber strain sensors **152** and the temperature sensor **52** are positioned so the sensitive portions are centered about the same axial location **160**.

Referring to FIG. **8**, a force sensing manipulator system **170** comprising a detector **172** such as an optical time-domain reflectometer (OTDR) and a steering mechanism **174** is schematically depicted in an embodiment of the invention. The force sensing manipulator system **170** may also be controlled and monitored by a controller or microprocessor **176**. A storage device **177** may be accessed by the microprocessor **176**. The storage device may comprise a programmable read-only memory (PROM) for providing program instructions and various constants and variables used in executing the force sensing operation. The storage device **177** may also include random access memory (RAM) and/or a writable medium such as a computer disk for storage of values computed by the microprocessor **176**.

The OTDR in this embodiment includes an electromagnetic source **178** and a receiver **180**, both operatively coupled to a plurality of fiber optics **44**. A splitter **182** may be operatively coupled with the electromagnetic source **178** that divides the electromagnetic radiation supplied by the electromagnetic source **178** into a transmitted component **184** and a reference component **186**. The transmitted component may be routed through a multiplexer **188** for interrogation of an

individual fiber optic (e.g. **44a**, **44b**, **44c**) and the fiber Bragg gratings **48**, **50** disposed thereon. A plurality of reflected components **190** may be returned from the fiber optics **44** and coupled with the reference component **186** for transmission into the receiver **180**.

The temperature sensor **52** may be operatively coupled to the distal portion **30** of the manipulator arm **20** to infer the temperature of the distal fiber Bragg gratings **50**. A signal conditioner **192** and digitizer **194** may be operatively coupled to the temperature sensor **52** to produce a digitized signal that may be monitored by the microprocessor **176**.

Referring to FIG. **8A**, an alternative arrangement is depicted for the fiber Bragg gratings **48**, **50** and for sensing the temperature of the distal fiber Bragg gratings **50**. In this embodiment, the flexing portion fiber Bragg gratings **48** and the distal fiber Bragg gratings **50** are all disposed on a single fiber optic **196**. The single fiber optic **196** may be routed multiple times along the length of the flexing portion **26** and the distal portion, and arranged so that the flexing portion fiber Bragg gratings **48** are grouped in sensor triplets **49** and so that at least one distal fiber Bragg grating **50** is disposed in the distal portion **30**.

In addition, a temperature sensing fiber Bragg grating **197** may be included on one the single fiber optic **196** and situated in the distal portion **30** proximate the distal fiber Bragg gratings **50**. The temperature sensing fiber Bragg grating **197** may be mechanically isolated from the distal portion **30** so as to be free of any strain caused by forces imparted on the distal portion **30**. In this way, the only dimensional and refractive index changes incurred by the temperature sensing fiber Bragg grating **197** may be due solely to temperature changes relative to a reference temperature. The temperature sensing fiber Bragg grating **197** may be interrogated with the other fiber Bragg gratings **48**, **50**, thus negating the need for separate routing of the temperature sensor **52** as well as the supporting instrumentation of the signal conditioner **192** and digitizer **194**. The technique of using temperature sensing fiber Bragg gratings is further detailed in U.S. Patent Application Publication 2007/0060847, assigned to the assignee of the instant application, the disclosure of which is incorporated by reference except for express definitions contained therein.

Returning to FIG. **8**, each of the fiber Bragg gratings **48**, **50** (and **197** when applicable) of each of the fiber optics **44** (or alternatively of the single fiber optic **196**) may be configured to reflect a distinct central wavelength when the fiber optic **44** or **196** is in an unstrained state. The distinct central wavelengths enable each of the fiber Bragg gratings **48**, **50** on the fiber optic **44** or **196** to be identified in a process referred to as wavelength division multiplexing (WDM). The WDM technique, or techniques akin thereto, are described in numerous publications, such as U.S. Pat. Nos. 5,798,521 to Froggatt and 6,256,090 to Chen et al. and U.S. Patent Application Publication No. 2007/0065077 to Childers et al., the disclosures of which are hereby incorporated by reference other than any claims or express definitions of terms specifically defined therein. In the WDM configuration, the electromagnetic source **178** is configured to sweep a range of wavelengths, with each of the fiber Bragg gratings **48**, **50** tuned to reflect light waves at a unique central wavelength within the swept wavelength range. The electromagnetic source **178** may comprise a solid state laser tunable over a range of wavelengths. An example electromagnetic source **178** is the Model SM130 tunable laser by Micron Optics, which may be configured for a tunable range 1519-nm to 1590-nm.

In another embodiment, the detector **172** may comprise an optical frequency-domain reflectometer (OFDR). The OFDR technique has been commercialized for numerous monitoring applications. Optical frequency-domain reflectometry enables sensors with the same nominal reflected wavelength

to be read with very high spatial resolution for spectral analysis. With the OFDR technique, the fiber Bragg gratings **48**, **50** may be interrogated with a swept wavelength source. Each of the fiber Bragg gratings **48**, **50** of a given fiber optic **44** may be spaced a unique distance from a reflector **198** operatively coupled with the fiber optic **44** or **198** located in the proximal portion **24**. In this way, each of the fiber Bragg gratings **48**, **50** combines with the respective reflector **198** to form an interferometer with a unique optical-path difference. When interrogated with an electromagnetic source, the interferometers modulate the reflected components **190** of each grating with a unique frequency that is directly dependent on the path difference. A summary of the OFDR method is presented in Appendices A and B, copies of which are attached hereto and incorporated by reference except for express definitions therein. Note that only one reflector **198** is required for the single fiber optic **198** configuration of FIG. **8A**.

Referring to FIG. **9**, a manipulator arm **20** is depicted using a plurality of Fabry-Perot resonators **199** to detect the force applied to the force transfer member **61**. The Fabry-Perot resonators may comprise commercially available fiber optic strain sensors, such as disclosed in U.S. Pat. Nos. 5,202,939 and 5,392,117 to Belleville, et al., disclosures of which are hereby incorporated by reference other than any express definitions of terms specifically defined therein. Other Fabry-Perot resonators may also be implemented, such as disclosed and depicted in U.S. patent application Ser. No. 11/753,429, a copy of which is attached hereto as Appendix C and which is incorporated by reference except for express definitions therein. U.S. patent application Ser. No. 11/753,429 is also assigned to the assignee of the instant application.

The Fabry-Perot resonators **199** may be selected to return a modulated signal from a selected portion of the spectrum of the electromagnetic source **178** that is functionally outside the operating ranges of the various flexing portion fiber Bragg gratings **48**, so as not to be attenuated by the flexing portion fiber Bragg gratings **48**. When the electromagnetic source **178** operates at this selected portion of the spectrum, the force sensing manipulator system **170** analyzes the returned modulated signal accordingly.

Functionally, the Fabry-Perot resonators **199** may be configured to provide certain advantages, including substantial insensitivity to bulk temperature changes and thermal gradients. The use of Fabry-Perot resonators may be more suitable with the OFDR technique.

A method for determining the position of the yoke portion **34** or the distal portion **30** or any arbitrary point on the elongate flexible body **22** is disclosed by Zhang, et al., "On SDM/WDM FBG Sensor Net for Shape Detection of Endoscope," Proceedings of the IEEE, International Conference on Mechatronics and Automation, July 2005, included herein as Appendix D, a copy of which is attached hereto and which is incorporated by reference except for express definitions therein. Other methods may also be utilized to infer position from the signals reflected from the flexing portion fiber Bragg gratings **48**, such as described by U.S. Published Patent Application 2007/0065077 to Childers et al., previously incorporated by reference herein.

Referring to FIGS. **10** through **13**, a method for determining shape and location from the strains experienced by the flexing portion fiber Bragg gratings **48** is described. The flexing portion **26** may be divided into segments **210**, each segment **210** being centered about one of the sensor triplets **49** disposed in the flexing portion **26** and including three core segments **212a**, **212b** and **212c**, one for each member of the sensor triplet **49**. The sensor triplets **49** may be evenly spaced segments along longitudinal axis **23** of the flexing portion fiber Bragg gratings **48**. Strain values for each flexing portion fiber Bragg grating **48** contained in the segment **210** may be used to compute a direction β of the bend angle θ and a bend

radius r for each of the segments **210**. Starting, for example, at the base **54** at the interface between the proximal portion **24** and the flexing portion **26** (FIG. **5**), the direction β and radius r data may be built up or accumulated to compute the location in the x, y, z coordinate system of each successive segment **210** along the flexing portion **26** and to define a new local coordinate system x', y', z' , herein referred to as the sensor frame coordinate system, for each successive sensor triplet **49**. In one embodiment, the sensor frame coordinate system has its origin at the center of the perimeter of the object for any given sensor triplet **49**. The circular arcs between each sensor triplet **49** on the flexing portion **26** may be interpolated. The geometry of the flexing portion **26** can thus be determined by repeating the accumulation, sensor frame coordinate system definition and interpolation process for each segment **210** and sensor triplet **49** along the length of the flexing portion **26**. The z' axis may point in the direction normal to the cross-section of the segment **210** and the y' axis may be aligned one of the fiber optics **44** (see FIGS. **10A** and **10B**).

For a given sensor triplet **49**, a trio of strain values $\epsilon_1, \epsilon_2, \epsilon_3$ may be detected, one from each member of the sensor triplet **49**. From the strain values $\epsilon_1, \epsilon_2, \epsilon_3$, one can calculate the direction β of the bend with respect to the x' axis as well as a bend radius r about an axis of rotation **214**, defined as the distance from the center of curvature to the center of the core perimeter (see FIG. **11**). Knowing the bend radius r and direction β for a particular segment **210** of the flexing portion **26**, computation of the coordinates of the end of the segment in the (x', y', z') coordinate system may be performed.

The beginning of the fiber segment **210** may be taken to be the origin of the (x', y', z') system. When there is no curvature, each core segment **44a** has a length s . When a curvature is introduced, each core is generally a different distance r_1, r_2 and r_3 from the center of curvature, as shown in FIG. **12B**. Because all of the core segments subtend the same curvature angle θ , each segment will generally have a unique length. The change in length due to bending the fiber is denoted as ds_1, ds_2 and ds_3 (FIG. **12B**).

The equations relating the change in length and radius of curvature of each fiber to the other fibers are derived as:

$$\theta = \frac{s + ds_1}{r_1} = \frac{s + ds_2}{r_2} = \frac{s + ds_3}{r_3} \quad \text{Eqn. (1)}$$

Because elastic strain (denoted by s) is defined as the ratio of the change in length of the fiber, ds to its unstretched length s (i.e. $\epsilon = ds/s$) the first part of Eqn. (1) may be written in terms of the measured strains:

$$\theta = \frac{s + ds_1}{r_1} = s \left(\frac{1 + \frac{ds_1}{s}}{r_1} \right) = s \left(\frac{1 + \epsilon_1}{r_1} \right) \quad \text{Eqn. (2)}$$

Accordingly, with respect to the other terms of Eqn. (1) the following expression results:

$$\frac{1 + \epsilon_1}{r_1} = \frac{1 + \epsilon_2}{r_2} = \frac{1 + \epsilon_3}{r_3} \quad \text{Eqn. (3)}$$

To solve Eqn. (3) for r and β , r_1, r_2 and r_3 are written in terms of r and β . This can be done by analyzing the geometry of the

fiber cross-section (FIG. **11**) and results in the following expressions for the radii of curvature for each of the fibers:

$$\begin{aligned} r_1 &= r + a \cdot \sin(\beta) \\ r_2 &= r + a \cdot \sin(\beta + \Phi_{12}) \\ r_3 &= r + a \cdot \sin(\beta - \Phi_{13}) \end{aligned} \quad \text{Eqn. (4)}$$

where a is the radial distance of the individual fiber Bragg gratings of a given sensor triplet **49** from the z -axis (FIG. **11**) Substituting Eqns. (4) to make substitutions into Eqns. (3), the following three equations are derived for r and β :

$$\begin{aligned} (1 + \epsilon_1)(r + a \cdot \sin(\beta + \Phi_{12})) &= (1 + \epsilon_2)(r + a \cdot \sin(\beta)) \\ (1 + \epsilon_1)(r + a \cdot \sin(\beta - \Phi_{13})) &= (1 + \epsilon_3)(r + a \cdot \sin(\beta)) \\ (1 + \epsilon_2)(r + a \cdot \sin(\beta - \Phi_{13})) &= (1 + \epsilon_3)(r + a \cdot \sin(\beta + \Phi_{12})) \end{aligned} \quad \text{Eqn. (5)}$$

Equation (5) may be solved for β using the trigonometric identity

$$\tan \beta = \frac{\epsilon_{13} \cdot \sin \phi_{12} + \epsilon_{12} \cdot \sin \phi_{13}}{\epsilon_{23} - \epsilon_{13} \cdot \sin \phi_{12} + \epsilon_{12} \cdot \sin \phi_{13}} \quad \text{Eqn. (6)}$$

where $\epsilon_{12} = \epsilon_2 - \epsilon_1$, $\epsilon_{13} = \epsilon_3 - \epsilon_1$ and $\epsilon_{23} = \epsilon_3 - \epsilon_2$.

Note that each term in the Eqn. (6) numerator and denominator is proportional to a strain difference. That is, the bend direction β is dependent only on the differential strains, not the absolute strain values.

The bend radius r can be computed in three different ways. Each of these formulae give the same solution for r , but in practice it is advantageous to implement at least two in case one of the differential strains β_{12}, β_{13} or β_{23} is zero.

$$r = \frac{a}{\epsilon_{12}} (\sigma_1 \cdot \sin(\beta + \phi_{12}) - \sigma_2 \cdot \sin(\beta)) \quad \text{Eqn. (7)}$$

$$r = \frac{a}{\epsilon_{13}} (\sigma_1 \cdot \sin(\beta - \phi_{13}) - \sigma_3 \cdot \sin(\beta))$$

$$r = \frac{a}{\epsilon_{23}} (\sigma_2 \cdot \sin(\beta - \phi_{13}) - \sigma_3 \cdot \sin(\beta + \phi_{12}))$$

where $\sigma_1 = (1 + \epsilon_1)$, $\sigma_2 = (1 + \epsilon_2)$ and $\sigma_3 = (1 + \epsilon_3)$.

From Eqn. (6), the domain of the bend direction β is $-\pi/2 < \beta < \pi/2$. The extra π radians appear in the calculation of the bend radius r . That is, if r is negative, simply negate r and add π to β . After this operation, $r > 0$ and $0 \leq \beta < 2\pi$. Also, where $\epsilon_1 = \epsilon_2 = \epsilon_3$, a special case arises where the bend direction β may be considered arbitrary because the bend radius r is infinite (zero curvature).

Resolution of a force vector (magnitude and direction) that is incident on the distal portion **30** may be inferred from strain measurements of the distal fiber Bragg gratings **50**. In one embodiment, one of the distal fiber Bragg gratings **50** may reflect a reference wavelength λ_r when the distal fiber Bragg grating **50** is at a reference temperature T_r at a reference time t_r when a reference or null measurement is performed. During operation, the distal fiber Bragg grating **50** may reflect a wavelength λ_t at time t relative to the reference time t_r . The wavelength λ_t from the distal fiber Bragg grating **50** may differ from the respective reference wavelength λ_r due to a change in the length αL of the distal fiber Bragg grating **50** relative to its length L at time t .

The change in the length αL may be caused by a strain on the distal fiber Bragg grating **50**, a temperature change that

induces a thermal expansion of the distal fiber Bragg grating **50**, or a combination thereof. An apparent strain $\Delta L/L$ may therefore be expressed as

$$\Delta L/L = C\epsilon \cdot (\lambda_r - \lambda_t) = \epsilon + \alpha \cdot \Delta T \quad \text{Eqn. (8)}$$

where

$$\Delta T = T_t - T_r \quad \text{Eqn. (9)}$$

and $C\epsilon$ is the coefficient of linearity between the FBG reflected wavelength and apparent strain, ϵ is the elastic strain imposed on the distal fiber Bragg grating **50**, α is an equivalent coefficient of thermal expansion for the distal fiber Bragg grating **50**, and ΔT is the difference between the temperature T_t of the distal fiber Bragg grating **50** at time t and the reference temperature T_r . The apparent strain $\Delta L/L$ is so named because, without knowledge of the temperature and thermal behavior of the optical fiber sensor, the ratio $\Delta L/L$ would appear to be the result of an elastic strain.

Generally, it is desirable to mathematically isolate the elastic strain ϵ because it is primarily due to axial forces imposed on the distal fiber Bragg grating **50**. Isolating the elastic strain gives

$$\epsilon = \Delta L/L - \alpha \cdot \Delta T = C\epsilon \cdot (\lambda_r - \lambda_t) - \alpha \cdot \Delta T \quad \text{Eqn. (10)}$$

For a plurality of distal fiber Bragg gratings **50**, Eqn. (10) may be expressed by

$$\epsilon_i = (\Delta L/L)_i = \alpha_i \cdot \Delta T_i = C\epsilon_i \cdot (\lambda_r - \lambda_t)_i - \alpha_i \cdot \Delta T_i \quad \text{Eqn. (11)}$$

where the subscript i denotes one of a plurality of distal fiber Bragg grating **50**.

But for the effects of temperature change on the optical fiber sensors, the apparent strain $\Delta L/L_i$ is equal to the elastic strains ϵ_i . Accordingly, the product $\alpha_i \cdot \Delta T_i$ may be considered a thermal bias component of the respective apparent strain $\Delta L/L_i$.

The equivalent coefficient of thermal expansion α is a parameter that is influenced by many factors. In some embodiments, α is influenced primarily by the coefficient of thermal expansion (CTE) of the distal portion **30**. The CTE of the fiber Bragg grating **50** may also be a contributing factor, as well as the CTE of the attachment mechanism (e.g. glue **162** or potting) between the distal portion **30** and the fiber Bragg grating **50**. The range of the CTEs of these components can vary substantially. For example, the CTE of the optical fiber Bragg grating **50** can be on the order of about 0.3 micrometers per Kelvin ($\mu\text{m}/\text{K}$), whereas the CTE of a distal portion **30** constructed of LCP may have a CTE from 1- to 4- $\mu\text{m}/\text{K}$. Some glues can have a CTE on the order of 60 $\mu\text{m}/\text{K}$.

Furthermore, the refractive index of the optical fiber Bragg grating **50** may be sensitive to changes in temperature. The sensitivity of the refractive index of some optical fibers is on the order of 10 picometers per Kelvin (pm/K). Depending on the configuration (e.g. geometry, CTEs of the various materials, sensitivity of the refractive index to temperature), the influence of the refractive index change may be dominant. For example, the resultant changes due to refractive index changes have been known to be an order of magnitude greater than the influence of CTE changes.

The true equivalent coefficient of thermal expansion α is generally affected by imperfections and/or non-repeatability of the assembly. For example, the equivalent coefficient of thermal expansion α of an optical fiber sensor may be substantially affected by minute differences in the amount of glue utilized to affect the bond. Accordingly, each of the fiber Bragg gratings **50** in a given strain sensing assembly is generally characterized by its own unique equivalent coefficient of thermal expansion α .

All of these thermal influences are rolled into the equivalent coefficient of thermal expansion α . Moreover, the complexity of the parameter may cause α to be non-linear. Accordingly, it is often preferable to determine the equivalent coefficient of thermal expansion α experimentally, such as by calibration, and for each optical fiber strain sensor in an assembly.

A method for determining the force exerted on the distal portion **30** from the distal fiber Bragg gratings **50** is now described. Consider a manipulator arm **20** having three fiber optic Bragg strain sensors embedded within the distal portion **30**, the distal portion **30** being comprised of a polymer, for example liquid crystal polymer (LCP). The total strain may be computed using:

$$\begin{bmatrix} \Delta L/L(1, t) \\ \Delta L/L(2, t) \\ \Delta L/L(3, t) \end{bmatrix} = \begin{bmatrix} C\epsilon & 0 & 0 & C\epsilon T \\ 0 & C\epsilon & 0 & C\epsilon T \\ 0 & 0 & C\epsilon & C\epsilon T \end{bmatrix} \cdot \begin{bmatrix} \lambda(1, t) \\ \lambda(2, t) \\ \lambda(3, t) \end{bmatrix} - \begin{bmatrix} \lambda(1, r) \\ \lambda(2, r) \\ \lambda(3, r) \end{bmatrix} \quad \text{Eqn. (12)}$$

where:

r = time when reference (zero) measurement is set;

t = time relative to reference time;

$\lambda(i, r)$ = reference wavelengths of the three fiber Bragg gratings $i=1-3$ at time r ;

$\lambda(i, t)$ = active wavelengths of the three fiber Bragg gratings $i=1-3$ at time t ;

$\Delta L/L(i, t)$ = apparent strain of the three fiber Bragg gratings $i=1-3$ at time t ;

$\Delta T(t)$ = temperature change at time t relative to a reference temperature at time r ;

$C\epsilon$ = coefficient of linearity between the reflected wavelength and strain; and

$C\epsilon T$ = coefficient of temperature compensation of the fiber Bragg gratings.

Where the temperature sensing fiber Bragg grating **197** is implemented to determine $\Delta T(t)$, Eqn. (12) may be expressed as

$$\begin{bmatrix} \Delta L/L(1, t) \\ \Delta L/L(2, t) \\ \Delta L/L(3, t) \\ \Delta T(t) \end{bmatrix} = \begin{bmatrix} C\epsilon & 0 & 0 & C\epsilon T \\ 0 & C\epsilon & 0 & C\epsilon T \\ 0 & 0 & C\epsilon & C\epsilon T \\ 0 & 0 & 0 & CT \end{bmatrix} \cdot \begin{bmatrix} \lambda(1, t) \\ \lambda(2, t) \\ \lambda(3, t) \\ \lambda(4, t) \end{bmatrix} - \begin{bmatrix} \lambda(1, r) \\ \lambda(2, r) \\ \lambda(3, r) \\ \lambda(4, r) \end{bmatrix} \quad \text{Eqn. (13)}$$

where $\lambda(4, r)$ and $\lambda(4, t)$ are, respectively, the reference and active wavelengths from the temperature sensing fiber Bragg grating **197**.

In general, the total strain includes a component due to thermal expansion of the deformable body arising from the difference between the measured temperature of the deformable body and a predetermined reference temperature. The elastic strain, which is a function of the applied force, therefore may be calculated using:

$$\begin{bmatrix} \epsilon(1, t) \\ \epsilon(2, t) \\ \epsilon(3, t) \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & -\alpha 1 \\ 0 & 1 & 0 & -\alpha 2 \\ 0 & 0 & 1 & -\alpha 3 \end{bmatrix} \cdot \begin{bmatrix} \Delta L/L(1, t) \\ \Delta L/L(2, t) \\ \Delta L/L(3, t) \\ \Delta T(t) \end{bmatrix} \quad \text{Eqn. (14)}$$

where $\epsilon(i, t)$ and α_i are, respectively, the elastic strain and the equivalent coefficient of thermal expansion of the three fiber Bragg gratings $i=1-3$ at time t .

Where temperature sensors 52 are provided for each of the trio of distal fiber Bragg gratings 50, the elastic strain may be calculated by:

$$\begin{bmatrix} \varepsilon(1, t) \\ \varepsilon(2, t) \\ \varepsilon(3, t) \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & -\alpha 1 & 0 & 0 \\ 0 & 1 & 0 & 0 & -\alpha 2 & 0 \\ 0 & 0 & 1 & 0 & 0 & -\alpha 3 \end{bmatrix} \cdot \begin{bmatrix} \Delta L/L(1, t) \\ \Delta L/L(2, t) \\ \Delta L/L(3, t) \\ \Delta T(1, t) \\ \Delta T(2, t) \\ \Delta T(3, t) \end{bmatrix} \quad \text{Eqn. (15)}$$

$$\text{or } \begin{bmatrix} \varepsilon(1, t) \\ \varepsilon(2, t) \\ \varepsilon(3, t) \end{bmatrix} = \begin{bmatrix} C & 0 & 0 & -\alpha 1 & 0 & 0 \\ 0 & C & 0 & 0 & -\alpha 2 & 0 \\ 0 & 0 & C & 0 & 0 & -\alpha 3 \end{bmatrix} \quad \text{Eqn. (16)}$$

$$\begin{pmatrix} \lambda(1, t) \\ \lambda(2, t) \\ \lambda(3, t) \\ T(1, t) \\ T(2, t) \\ T(3, t) \end{pmatrix} = \begin{pmatrix} \lambda(1, r) \\ \lambda(2, r) \\ \lambda(3, r) \\ T(1, r) \\ T(2, r) \\ T(3, r) \end{pmatrix}$$

where T(i,r) are the inferred reference temperature readings of the three fiber Bragg gratings i=1-3 at time r and T(i,t) are the inferred active temperature readings of the three fiber Bragg gratings i=1-3 at time t. Both T(i,r) and T(i,t) may be inferred from the plurality of temperature sensors 52.

The elastic strains are related to the internal forces experienced by the optical fiber sensors as a function of both the physical dimensions of, and the material properties of, the deformable body:

$$\begin{bmatrix} \varepsilon(1, t) \\ \varepsilon(2, t) \\ \varepsilon(3, t) \end{bmatrix} = \begin{bmatrix} 1 & y_1 & -x_1 \\ 1 & y_2 & -x_2 \\ 1 & y_3 & -x_3 \end{bmatrix} \cdot \begin{bmatrix} \frac{1}{E_T \cdot A} & 0 & 0 \\ 0 & \frac{1}{E_F \cdot I_x} & 0 \\ 0 & 0 & \frac{1}{E_F \cdot I_y} \end{bmatrix} \quad \text{Eqn. (17)}$$

$$\begin{bmatrix} N(z, t) \\ M(x, t) \\ M(y, t) \end{bmatrix}$$

where:

xi and yi=coordinate locations of the distal fiber Bragg gratings 50 relative to a reference point (e.g. center of gravity) of the catheter cross-section;

E_T=equivalent tension/compression Young modulus of the catheter;

E_F=equivalent flexural Young modulus of the catheter;

I_x=moment of inertia of the catheter cross-section about the x-axis;

I_y=moment of inertia of the catheter cross-section about the y-axis;

N(z,t)=normal force in the direction of the z-axis at time t;

M(x,t)=bending moment about the x-axis at time t; and

M(y,t)=bending moment about the y-axis at time t.

Equation (17) may be rearranged to solve for the internal forces as a function of the elastic strain:

$$\begin{bmatrix} N(z, t) \\ M(x, t) \\ M(y, t) \end{bmatrix} = \begin{bmatrix} E_T \cdot A & 0 & 0 \\ 0 & E_F \cdot I_x & 0 \\ 0 & 0 & E_F \cdot I_y \end{bmatrix} \quad \text{Eqn. (18)}$$

$$\begin{bmatrix} 1 & y_1 & -x_1 \\ 1 & y_2 & -x_2 \\ 1 & y_3 & -x_3 \end{bmatrix}^{-1} \cdot \begin{bmatrix} \varepsilon(1, t) \\ \varepsilon(2, t) \\ \varepsilon(3, t) \end{bmatrix}$$

It remains only to relate the internal forces N(z,t), M(x,t) and M(y,t) experienced by the optical fiber sensors to the external contact or reaction forces F exerted on the distal extremity of the end effector 28. These forces are computed based on the positions of the optical fiber sensors from the exterior wall of the deformable body, assuming the deformable body is substantially incompressible:

$$\begin{bmatrix} F(x, t) \\ F(y, t) \\ F(z, t) \end{bmatrix} = \begin{bmatrix} 0 & 0 & -\frac{1}{d} \\ 0 & \frac{1}{d} & 0 \\ -1 & 0 & 0 \end{bmatrix} \cdot \begin{bmatrix} N(z, t) \\ M(x, t) \\ M(y, t) \end{bmatrix} \quad \text{Eqn. (19)}$$

where:

F(x,t)=lateral touching force parallel to the x-axis at time t (with opposite sense);

F(y,t)=lateral touching force parallel to the y-axis at time t (with opposite sense);

F(z,t)=normal touching force parallel to the z-axis at time t (with opposite sense, compression being positive); and

d=axial distance between the touching point of the lateral forces and the cross-section of the catheter centered about the distal fiber Bragg gratings 50.

The axial distance d and the forces F(x,t), F(y,t) and F(z,t) are depicted in FIG. 3.

Having solved for the normal force F(z,t) and the lateral forces F(x,t) and F(y,t), a normal force F_{norm}(t) at time t and a transverse force F_{trans}(t) at time t of the touching force vector F may be computed:

$$F_{norm}(t)=F(z,t) \quad \text{Eqn. (20)}$$

$$F_{trans}(t)=\sqrt{F(x,t)^2+F(y,t)^2} \quad \text{Eqn. (21)}$$

An angle γt of incidence of the transverse force F_{trans}(t) at time t and relative to the z-axis may be computed from Table I:

TABLE I

F(x,t)	F(y,t)	γt
≥0	≥0	arcsin[F(y,t)/F _{trans} (t)]
<0	≥0	π - arcsin[F(y,t)/F _{trans} (t)]
<0	<0	π + arcsin[F(y,t)/F _{trans} (t)]
≥0	<0	2 * π - arcsin[F(y,t)/F _{trans} (t)]

Many of the values employed in Eqns. (8) to (18) are related to the material properties of the deformable body or optical fiber sensors, such as the Bragg wavelengths, thermal expansion coefficients and elastic moduli of the deformable body. Other values, such as the distances between the optical

fiber sensors and the external surface of the deformable body may be subject to variations as a consequence of the manufacturing process employed.

To ensure the accuracy of the computed force vector, specific information (e.g. calibration and geometric information) for each deformable body may be stored in the storage device 177. Generally, the information may take the form of a data file that is input to the storage device 177. For example, storage device 177 may comprise a memory chip associated with the manipulator 20 in which such information is stored, or a bar code or a RFID tag located on the manipulator arm 20 or the packaging for the manipulator arm 20. Alternatively, data specific to the manipulator arm may be uploaded to storage device 177 from an external computer via an item of removable storage (e.g., CD) or via a secure download from the manufacturer's website.

The information specific to each deformable body may be obtained during a calibration step, conducted during manufacture of the deformable body, by subjecting the manipulator arm 20 to a series of known forces. In this case, the foregoing equations may be collapsed so the normal and transverse forces may be computed directly from a force-to-wavelength conversion matrix:

$$F(t)=K(\lambda(t)-\lambda_0) \quad \text{Eqn. (22)}$$

where:

F(t) is the vector of forces [F(x,t), F(y,t), F(z,t)];

$\lambda(t)$ is the vector of wavelengths [$\lambda(1,t)$, $\lambda(2,t)$, $\lambda(3,t)$] measured for the individual sensors at time t;

λ_0 is the reference vector of wavelengths [$\lambda(1,r)$, $\lambda(2,r)$, $\lambda(3,r)$] measured for the individual sensors at time r with zero applied force; and

K is a matrix computed when the deformable body is subjected to the series of known forces.

During the calibration step of manufacture, the deformable body may be subjected to the following forces in series: (1) a purely axial force of known magnitude Fa; (2) a lateral force of known magnitude Fb applied perpendicular to the axial force Fa; and (3) a lateral force of known magnitude Fc applied perpendicular to the axial force Fa and 190 degrees to the orientation of force Fb. When all of the forces Fa, Fb and Fc, and wavelength vectors $\lambda(t)$ and λ_0 are known, the force-to-strain conversion matrix K may be computed as:

$$K=F(\lambda(t)-\lambda_0)^{-1} \quad \text{Eqn. (23)}$$

or:

$$\begin{bmatrix} Fa & 0 & 0 \\ 0 & Fb & 0 \\ 0 & 0 & Fc \end{bmatrix} \begin{bmatrix} (\lambda 1a - \lambda^0 1) & (\lambda 1b - \lambda^0 1) & (\lambda 1c - \lambda^0 1) \\ (\lambda 2a - \lambda^0 2) & (\lambda 2b - \lambda^0 2) & (\lambda 2c - \lambda^0 2) \\ (\lambda 3a - \lambda^0 3) & (\lambda 3b - \lambda^0 3) & (\lambda 3c - \lambda^0 3) \end{bmatrix}^{-1} = \quad \text{Eqn. (24)}$$

$$\begin{bmatrix} k11 & k12 & k13 \\ k21 & k22 & k23 \\ k31 & k32 & k33 \end{bmatrix}$$

The force-to-strain conversion matrix K may be stored in the storage device 177 for access by the microprocessor 176 and associated with the corresponding manipulator arm, as described herein above. Once matrix K is provided for a given manipulator arm, the normal force Fnorm(t), transverse force and angle of application of the transverse force may be computed as described above and using Table I.

The values for the normal force, transverse force and angle of application of the transverse force Ftrans(t), computed as

described above, may be output as numerical values, for example to a display monitor. In addition, a graphic including a variable size or colored arrow may be output pointing at a position on the circumference of a circle to visualize the magnitude and direction of the transverse force applied to the distal extremity of the deformable body. By monitoring an active display, the operator may continuously obtain feedback concerning the contact forces applied to the distal extremity of the deformable body.

References to relative terms such as upper and lower, front and back, left and right, or the like, are intended for convenience of description and are not contemplated to limit the invention, or its components, to any specific orientation. All dimensions depicted in the figures may vary with a potential design and the intended use of a specific embodiment of this invention without departing from the scope thereof.

Each of the additional figures and methods disclosed herein may be used separately, or in conjunction with other features and methods, to provide improved devices, systems and methods for making and using the same. Therefore, combinations of features and methods disclosed herein may not be necessary to practice the invention in its broadest sense and are instead disclosed merely to particularly describe representative embodiments of the invention.

For purposes of interpreting the claims for the present invention, it is expressly intended that the provisions of Section 112, sixth paragraph of 35 U.S.C. are not to be invoked unless the specific terms "means for" or "step for" are recited in the subject claim.

What is claimed is:

1. A method for determining a location of and a contact force exerted on an end effector of a catheter during use in a medical procedure, comprising:

providing a manipulator including a flexing portion and a distal portion, at least one distal fiber Bragg grating being disposed in said distal portion and operatively coupled to said distal portion to sense said contact force exerted on said end effector, a plurality of flexing portion fiber Bragg gratings being disposed within said flexing portion and conforming to a shape of said flexing portion, said plurality of flexing portion fiber Bragg gratings defining a plurality of sensor triplets, each sensor triplet being disposed within a corresponding segment of said flexing portion;

causing electromagnetic radiation to propagate through said at least one distal fiber Bragg grating and said plurality of sensor triplets;

measuring a plurality of reflected components of said electromagnetic radiation, the reflected components being reflected from said at least one distal fiber Bragg gratings and from said flexing portion fiber Bragg gratings of said sensor triplets;

determining a plurality of bend direction and bend radius values, one for each of said corresponding segments of said flexing portion, based on said reflected components returned by said plurality of sensor triplets;

accumulating said plurality of bend direction and bend radius values from a starting point on said flexing portion to determine a location in three-dimensional space for each of said corresponding segments;

determining at least one elastic strain, one for each of said at least one distal fiber Bragg grating, from said reflected components returned by said at least one distal fiber Bragg grating; and

resolving said contact force exerted on said end effector from said at least one elastic strain.

2. The method of claim 1, wherein said distal portion of said manipulator provided in the step of providing said manipulator includes a yoke portion, said at least one distal fiber Bragg grating of said distal portion being distal to said yoke portion.

3. The method of claim 2, further comprising:

providing a steering mechanism operatively coupled with said yoke portion and extending through said flexing portion for manipulation of said flexing portion.

4. The method of claim 1, wherein said manipulator included in the step of providing a manipulator includes a temperature sensor disposed in said distal portion, said temperature sensor including a fiber Bragg grating, the method further comprising:

causing electromagnetic radiation to propagate through said fiber Bragg grating of said temperature sensor; measuring a reflected component of said electromagnetic radiation returned from said fiber Bragg grating of said temperature sensor;

inferring an apparent strain based on said reflected component of said electromagnetic radiation returned from said fiber Bragg grating of said temperature sensor; and compensating said at least one elastic strain based on said apparent strain.

5. A method for determining a location of and a contact force exerted on an end effector of a catheter during use in a medical procedure, the method comprising:

providing a catheter for use in a medical procedure, said catheter comprising a base, a flexing portion extending from said base, a distal portion extending from said flexing portion, said distal portion including a yoke portion, a steering mechanism operatively coupled with said yoke portion and extending through said flexing portion for manipulation of said flexing portion, and a plurality of fiber optics extending through at least said flexing portion and being operatively coupled with said yoke portion, wherein at least two of said plurality of fiber optics include a plurality of flexing portion fiber optic strain sensors positioned to coincide with said flexing portion, and wherein at least one of said plurality of fiber optics terminates in said distal portion distal to said yoke portion and having a force sensing optical fiber strain sensor operatively coupled with said distal portion;

providing an electromagnetic source adapted for connection with said plurality of fiber optics to deliver electro-

magnetic radiation to said plurality of flexing portion fiber optic strain sensor and the at least one force sensing optical fiber strain sensor;

providing a receiver operatively coupled to said plurality of fiber optics for detection of electromagnetic radiation returned from said plurality of flexing portion fiber optic strain sensors and for detection of electromagnetic radiation returned from the at least one force sensing optical fiber strain sensor; and

providing a microprocessor operatively coupled with said receiver to process signals received from said receiver, said microprocessor being operatively coupled with and executing instructions contained on a storage device, said instructions comprising:

acquiring shape information based on said electromagnetic radiation returned from said plurality of flexing portion fiber optic strain sensors; and

acquiring contact force information based on said electromagnetic radiation returned from the at least one force sensing fiber optic strain sensor.

6. The method of claim 5, wherein said instructions provided in the step of providing said microprocessor further comprises:

determining a plurality of bend direction and bend radius values based on said shape information;

accumulating said plurality of bend direction and bend radius values from a starting point located on one of said base and said flexing portion to determine a location in three-dimensional space for each of said plurality of flexing portion fiber optic strain sensors; and

resolving said contact force exerted on said end effector based on said force information.

7. The method of claim 5, wherein said flexing portion fiber optic strain sensors provided in the step of providing a catheter include fiber Bragg gratings.

8. The method of claim 7, wherein the at least one force sensing fiber optic strain sensor provided in the step of providing a catheter includes one of a fiber Bragg grating and a Fabry-Perot resonator.

9. The method of claim 5, wherein at least one of said plurality of fiber optics provided in the step of providing a catheter includes both said plurality of flexing portion fiber optic strain sensors and said force sensing optical fiber strain sensor.

* * * * *

专利名称(译)	带有身体位置和远端力感应的细长手术机械手		
公开(公告)号	US8622935	公开(公告)日	2014-01-07
申请号	US12/127657	申请日	2008-05-27
[标]申请(专利权)人(译)	LEO GIOVANNI		
申请(专利权)人(译)	LEO , GIOVANNI		
当前申请(专利权)人(译)	ENDONSENSE SA		
[标]发明人	LEO GIOVANNI		
发明人	LEO, GIOVANNI		
IPC分类号	A61B5/117 A61M37/00 A61B5/00 A61M31/00 A61B5/103		
CPC分类号	A61B5/01 A61M37/00 A61B5/103 A61B5/00 A61B5/117 A61B5/6843 A61B5/0084 A61M31/00 A61M25/0158 A61B34/30 A61B34/70		
代理机构(译)	华达THUENTE彼得森P.A.		
优先权	60/931762 2007-05-25 US		
外部链接	Espacenet USPTO		

摘要(译)

细长的手术操纵器设备和操作方法使得能够确定细长的外科手术操纵器的柔性部分的形状和/或其上的任意点的位置，以及施加在其上的远端部分上的接触力的量度。机械手。多个光纤可操作地与操纵器耦合，每个光纤包括多个光纤布拉格光栅，用于确定形状和/或位置。每个光纤还包括光纤应变仪，例如布拉格光栅或法布里 - 珀罗谐振器，其位于细长外科手术操纵器的远端部分，其与与操纵器的弯曲相关联的应变隔离。因此，远端部分处的光纤应变仪可用于检测施加在远端部分上的力矢量（大小和方向）。

