



US010159533B2

(12) **United States Patent**
Moll et al.

(10) **Patent No.:** **US 10,159,533 B2**
(45) **Date of Patent:** **Dec. 25, 2018**

(54) **SURGICAL SYSTEM WITH CONFIGURABLE
RAIL-MOUNTED MECHANICAL ARMS**

(71) Applicant: **Auris Health, Inc.**, Redwood City, CA
(US)

(72) Inventors: **Frederic Moll**, San Francisco, CA
(US); **Alan Yu**, Union City, CA (US)

(73) Assignee: **Auris Health, Inc.**, Redwood City, CA
(US)

(*) Notice: Subject to any disclaimer, the term of this
patent is extended or adjusted under 35
U.S.C. 154(b) by 0 days.

(21) Appl. No.: **15/094,179**

(22) Filed: **Apr. 8, 2016**

(65) **Prior Publication Data**

US 2016/0296294 A1 Oct. 13, 2016

Related U.S. Application Data

(60) Provisional application No. 62/145,418, filed on Apr.
9, 2015.

(51) **Int. Cl.**
A61B 17/00 (2006.01)
A61G 13/04 (2006.01)
(Continued)

(52) **U.S. Cl.**
CPC **A61B 34/30** (2016.02); **A61G 13/04**
(2013.01); **A61G 13/06** (2013.01); **A61G**
13/10 (2013.01);
(Continued)

(58) **Field of Classification Search**
CPC A61G 13/00; A61G 13/0036; A61G
13/0045; A61G 13/0054; A61G 13/0063;
(Continued)

(56) **References Cited**

U.S. PATENT DOCUMENTS

5,013,018 A 5/1991 Sicek
5,160,106 A * 11/1992 Monick A61G 13/101
248/231.71

(Continued)

FOREIGN PATENT DOCUMENTS

CN 202314134 U 7/2012

OTHER PUBLICATIONS

International search report and written opinion dated Jul. 13, 2016
for PCT/US2016/026783.

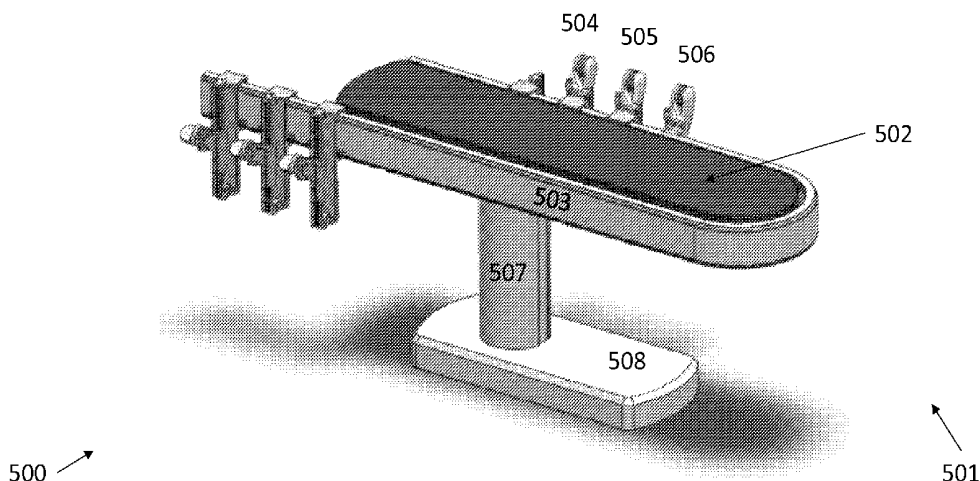
Primary Examiner — Nicholas F Polito

(74) *Attorney, Agent, or Firm* — Knobbe, Martens, Olson
& Bear, LLP

(57) **ABSTRACT**

A robotic surgical system comprises a horizontal platform to support a patient, a rail positioned about the horizontal platform, a carriage operatively coupled to and configured to translate along the rail, and a robotic arm operatively coupled to the carriage and translated about the patient by the rail. The robotic arm is configured to operate on the patient in a variety of positions provided by the translating carriage. The rail provides a rounded path for the carriage, such as a U-shaped path. The U-shaped path may comprise a first leg and a second leg, the first leg longer than the second leg. Furthermore, the system may comprise a plurality of carriages operatively coupled to the rail and a plurality of robotic arms. Also, the system may further comprise a central base which the horizontal platform can articulate relative to, such as by translating horizontally or vertically, rotating, or tilting.

19 Claims, 20 Drawing Sheets



(51)	Int. Cl.		9,737,371 B2	8/2017	Romo et al.	
	<i>A61G 13/10</i> (2006.01)		9,737,373 B2	8/2017	Schuh	
	<i>A61B 34/30</i> (2016.01)		9,744,335 B2	8/2017	Jiang	
	<i>A61G 13/06</i> (2006.01)		9,763,741 B2	9/2017	Alvarez et al.	
	<i>A61B 90/57</i> (2016.01)		9,788,910 B2	10/2017	Schuh	
(52)	U.S. Cl.		9,844,412 B2	12/2017	Bogusky et al.	
	CPC ... <i>A61B 2034/304</i> (2016.02); <i>A61B 2090/571</i>		9,867,635 B2	1/2018	Alvarez et al.	
	(2016.02); <i>A61G 13/101</i> (2013.01)		2002/0162926 A1 *	11/2002	Nguyen	A61G 13/101 248/229.25
			2002/0170116 A1 *	11/2002	Borders	A61B 6/0457 5/600
(58)	Field of Classification Search		2006/0149418 A1	7/2006	Anvari	
	CPC <i>A61G 13/0072</i> ; <i>A61G 13/0081</i> ; <i>A61G</i>		2006/0200026 A1	9/2006	Wallace et al.	
	<i>13/10</i> ; <i>A61G 13/101</i> ; <i>A61G 13/107</i> ;		2008/0027464 A1	1/2008	Moll et al.	
	<i>A61G 13/06</i> ; <i>A61B 34/30</i> ; <i>A61B</i>		2008/0039867 A1	2/2008	Feussner	
	<i>2090/571</i>		2008/0082109 A1	4/2008	Moll et al.	
	See application file for complete search history.		2008/0167750 A1	7/2008	Stahler	
(56)	References Cited		2008/0195081 A1	8/2008	Moll et al.	
	U.S. PATENT DOCUMENTS		2008/0218770 A1	9/2008	Moll et al.	
			2009/0036900 A1	2/2009	Moll	
			2009/0062602 A1	3/2009	Rosenberg et al.	
			2009/0163928 A1	6/2009	Schena	
	5,259,365 A	11/1993 Nishikori et al.	2011/0028894 A1	2/2011	Foley et al.	
	5,555,897 A *	9/1996 Lathrop, Jr. <i>A61B 34/76</i>	2011/0238083 A1	9/2011	Moll et al.	
		5/600	2011/0270273 A1	11/2011	Moll et al.	
	5,597,146 A	1/1997 Putman	2012/0191079 A1	7/2012	Moll et al.	
	5,762,458 A *	6/1998 Wang <i>B25J 9/1689</i>	2012/0191083 A1	7/2012	Moll et al.	
		414/1	2012/0191086 A1	7/2012	Moll et al.	
	5,926,875 A	7/1999 Okamoto et al.	2012/0253332 A1	10/2012	Moll	
	5,944,476 A	8/1999 Bacchi et al.	2012/0266379 A1 *	10/2012	Hushek	A61G 7/1019 5/86.1
	6,170,102 B1	1/2001 Kreuzer				
	6,202,230 B1	3/2001 Borders	2012/0296161 A1	11/2012	Wallace et al.	
	6,804,581 B2 *	10/2004 Wang <i>A61B 34/70</i>	2013/0041219 A1	2/2013	Hasegawa et al.	
		600/101	2013/0072787 A1	3/2013	Wallace et al.	
	7,789,874 B2	9/2010 Yu et al.	2013/0190741 A1	7/2013	Moll et al.	
	7,850,642 B2	12/2010 Moll et al.	2014/0142591 A1	5/2014	Alvarez et al.	
	7,963,288 B2	6/2011 Rosenberg et al.	2014/0309649 A1	10/2014	Alvarez et al.	
	7,972,298 B2	7/2011 Wallace et al.	2014/0357984 A1	12/2014	Wallace et al.	
	7,974,681 B2	7/2011 Wallace et al.	2014/0364870 A1	12/2014	Alvarez et al.	
	7,976,539 B2	7/2011 Hlavka et al.	2014/0379000 A1	12/2014	Romo et al.	
	7,979,157 B2	7/2011 Anvari	2015/0051592 A1	2/2015	Kintz	
	8,005,537 B2	8/2011 Hlavka et al.	2015/0101442 A1	4/2015	Romo	
	8,021,326 B2	9/2011 Moll et al.	2015/0119638 A1	4/2015	Yu et al.	
	8,052,636 B2	11/2011 Moll et al.	2015/0164594 A1	6/2015	Romo et al.	
	8,108,069 B2	1/2012 Stahler et al.	2015/0164596 A1	6/2015	Romo	
	8,146,874 B2	4/2012 Yu	2015/0335480 A1	11/2015	Alvarez et al.	
	8,172,747 B2	5/2012 Wallace et al.	2016/0001038 A1	1/2016	Romo et al.	
	8,190,238 B2	5/2012 Moll et al.	2016/0270865 A1	9/2016	Landey et al.	
	8,257,303 B2	9/2012 Moll et al.	2016/0279394 A1	9/2016	Moll et al.	
	8,311,626 B2	11/2012 Hlavka et al.	2016/0287279 A1	10/2016	Bovay et al.	
	8,394,054 B2	3/2013 Wallace et al.	2016/0296294 A1	10/2016	Moll et al.	
	8,409,136 B2	4/2013 Wallace et al.	2016/0374541 A1	12/2016	Agrawal et al.	
	8,409,172 B2	4/2013 Moll et al.	2017/0007337 A1	1/2017	Dan	
	8,498,691 B2	7/2013 Moll et al.	2017/0065364 A1	3/2017	Schuh et al.	
	8,617,102 B2	12/2013 Moll et al.	2017/0065365 A1	3/2017	Schuh	
	8,801,661 B2	8/2014 Moll et al.	2017/0086929 A1	3/2017	Moll et al.	
	8,897,920 B2	11/2014 Wang et al.	2017/0100199 A1	4/2017	Yu et al.	
	8,926,603 B2	1/2015 Hlavka et al.	2017/0119411 A1	5/2017	Shah	
	8,968,333 B2	3/2015 Yu et al.	2017/0119412 A1	5/2017	Noonan et al.	
	8,974,408 B2	3/2015 Wallace et al.	2017/0119413 A1	5/2017	Romo	
	9,078,686 B2	7/2015 Schena	2017/0119481 A1	5/2017	Romo et al.	
	9,314,306 B2	4/2016 Yu	2017/0165011 A1	6/2017	Bovay et al.	
	9,326,822 B2	5/2016 Lewis et al.	2017/0172673 A1	6/2017	Yu et al.	
	9,358,076 B2	6/2016 Moll et al.	2017/0202627 A1	7/2017	Sramek et al.	
	9,408,669 B2	8/2016 Kokish et al.	2017/0209073 A1	7/2017	Sramek et al.	
	9,452,018 B2	9/2016 Yu	2017/0215978 A1	8/2017	Wallace et al.	
	9,457,168 B2	10/2016 Moll et al.	2017/0290631 A1	10/2017	Lee et al.	
	9,504,604 B2	11/2016 Alvarez	2017/0333679 A1	11/2017	Jiang	
	9,561,083 B2	2/2017 Yu et al.	2017/0340396 A1	11/2017	Romo et al.	
	9,566,201 B2	2/2017 Yu	2017/0365055 A1	12/2017	Mintz et al.	
	9,622,827 B2	4/2017 Yu et al.	2017/0367782 A1	12/2017	Schuh et al.	
	9,629,682 B2	4/2017 Wallace et al.	2018/0025666 A1	1/2018	Ho et al.	
	9,636,184 B2	5/2017 Lee et al.	2018/0055583 A1	3/2018	Schuh et al.	
	9,713,509 B2	7/2017 Schuh et al.				
	9,727,963 B2	8/2017 Mintz et al.				

* cited by examiner

* cited by examiner

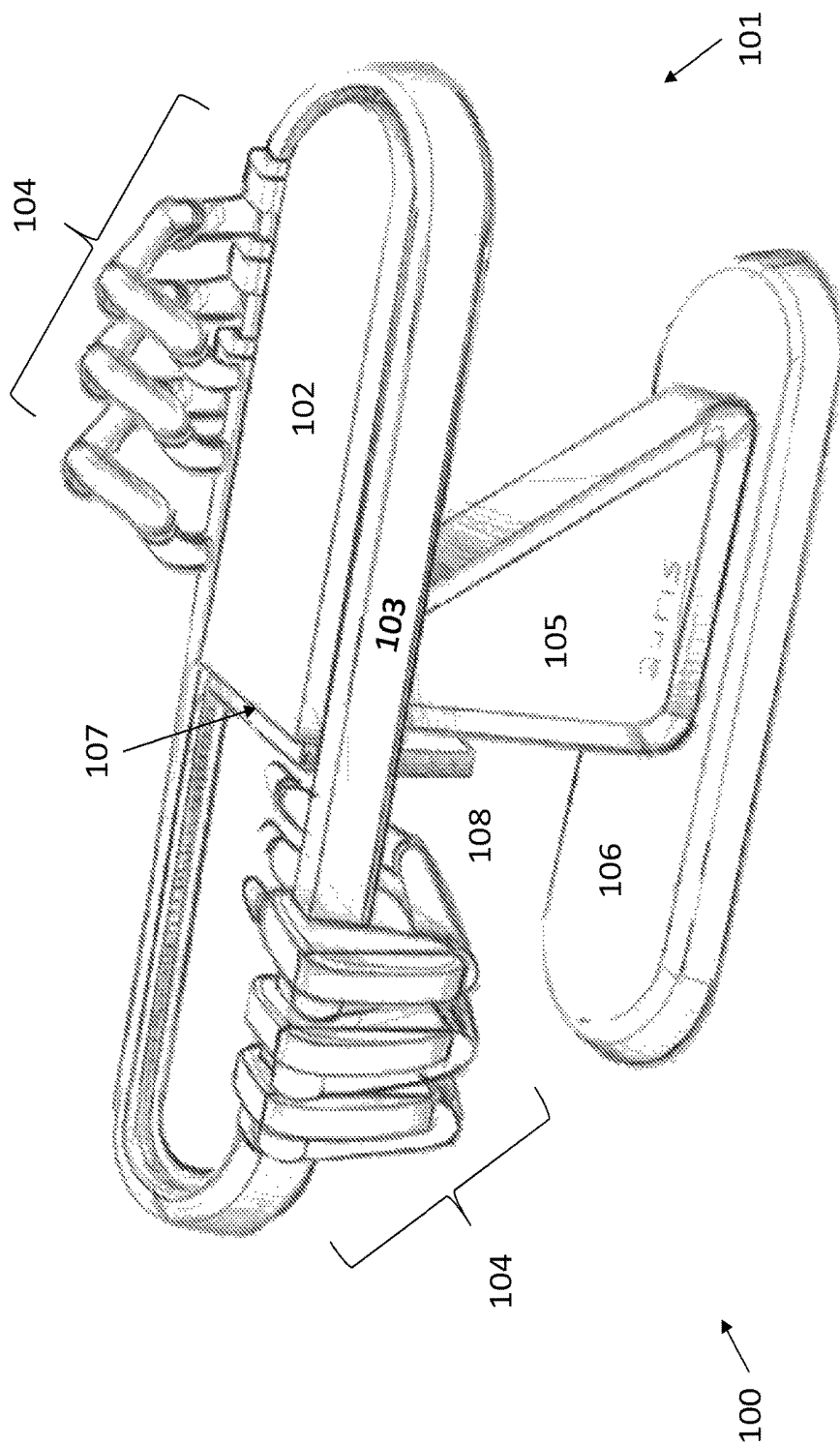


FIG. 1

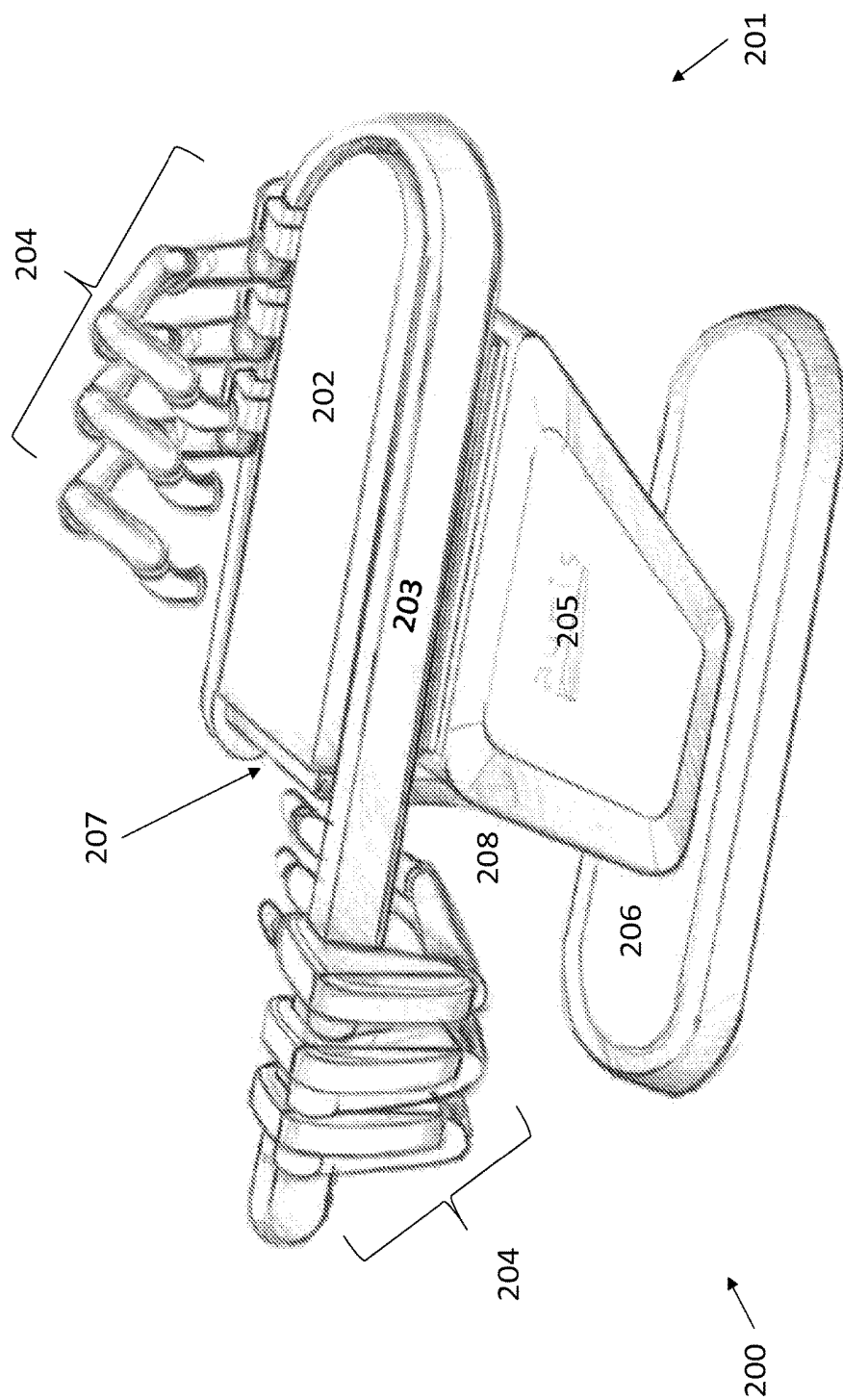


FIG. 2

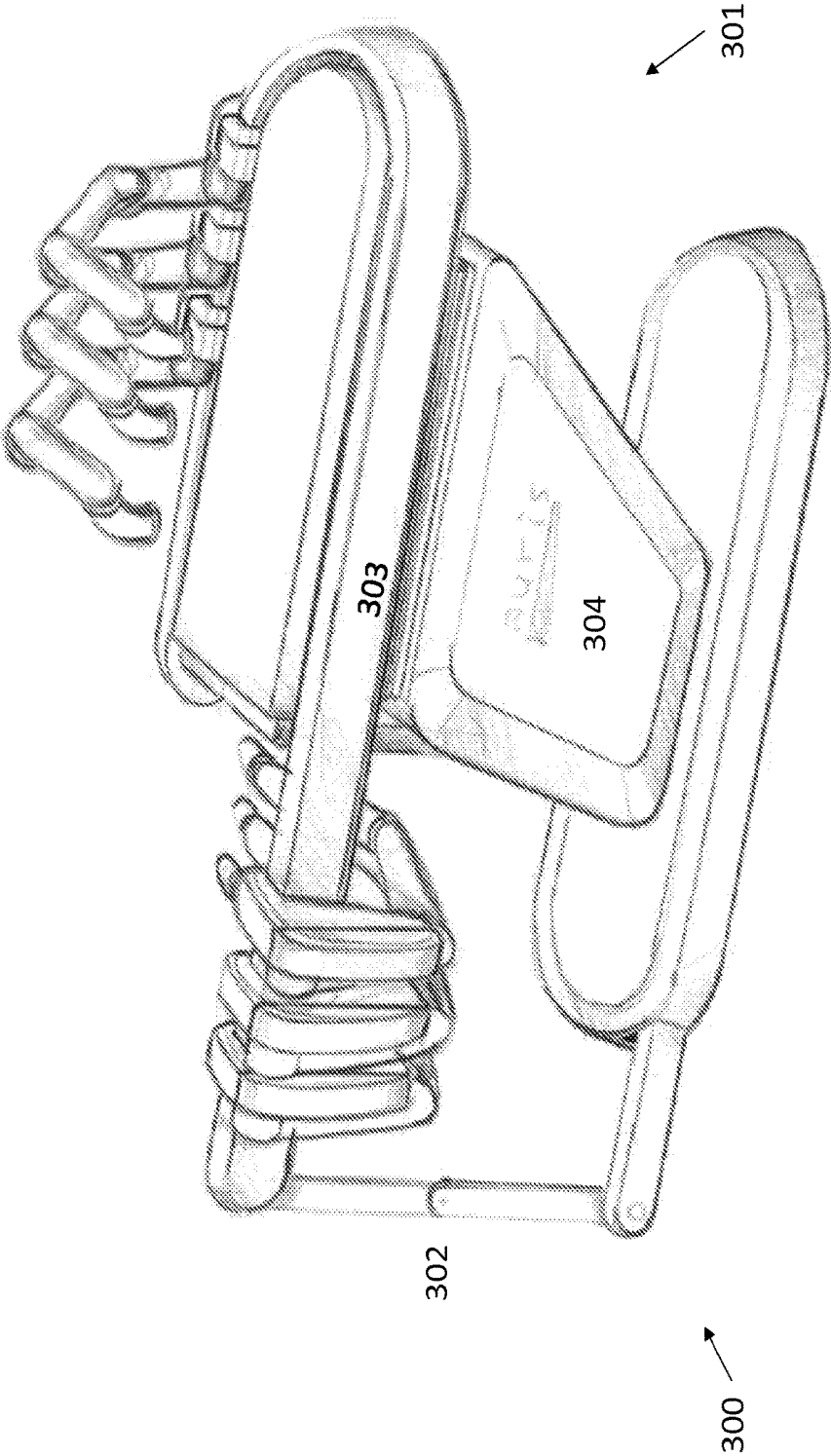


FIG. 3

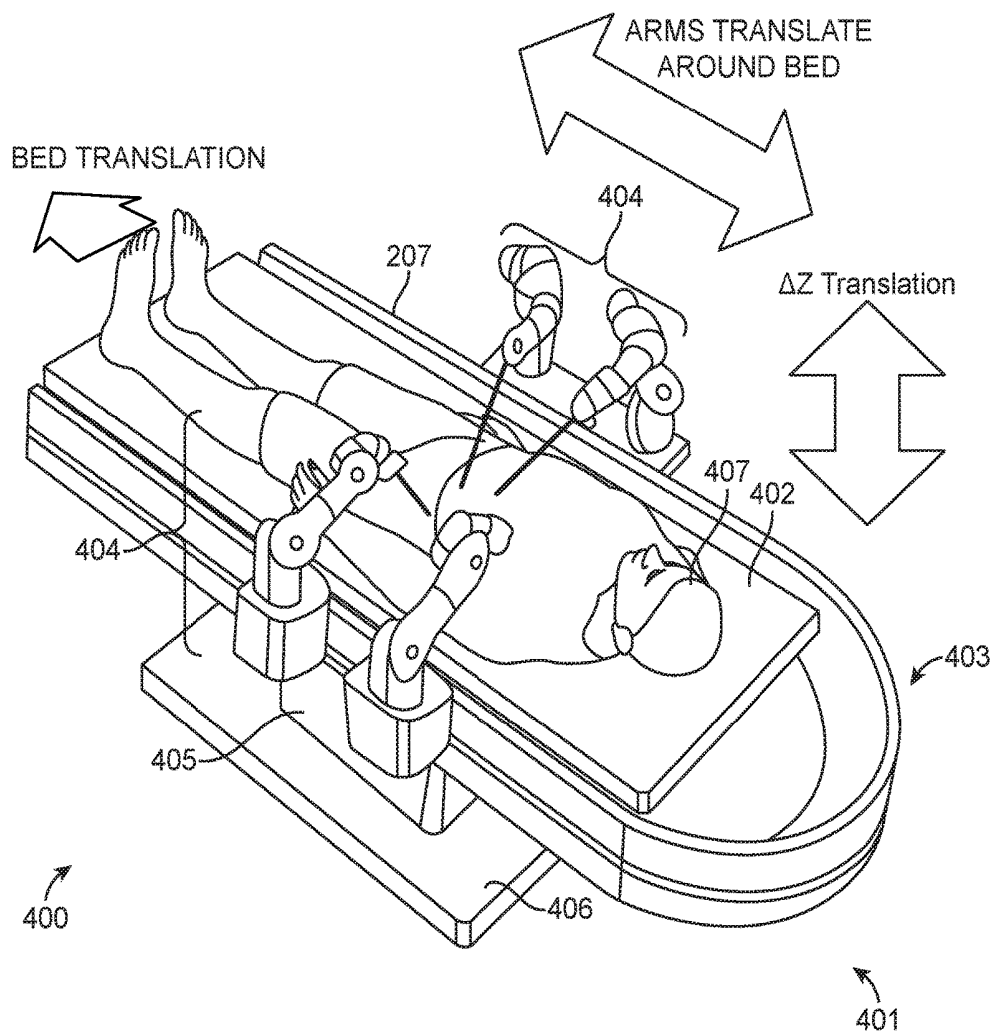


FIG. 4

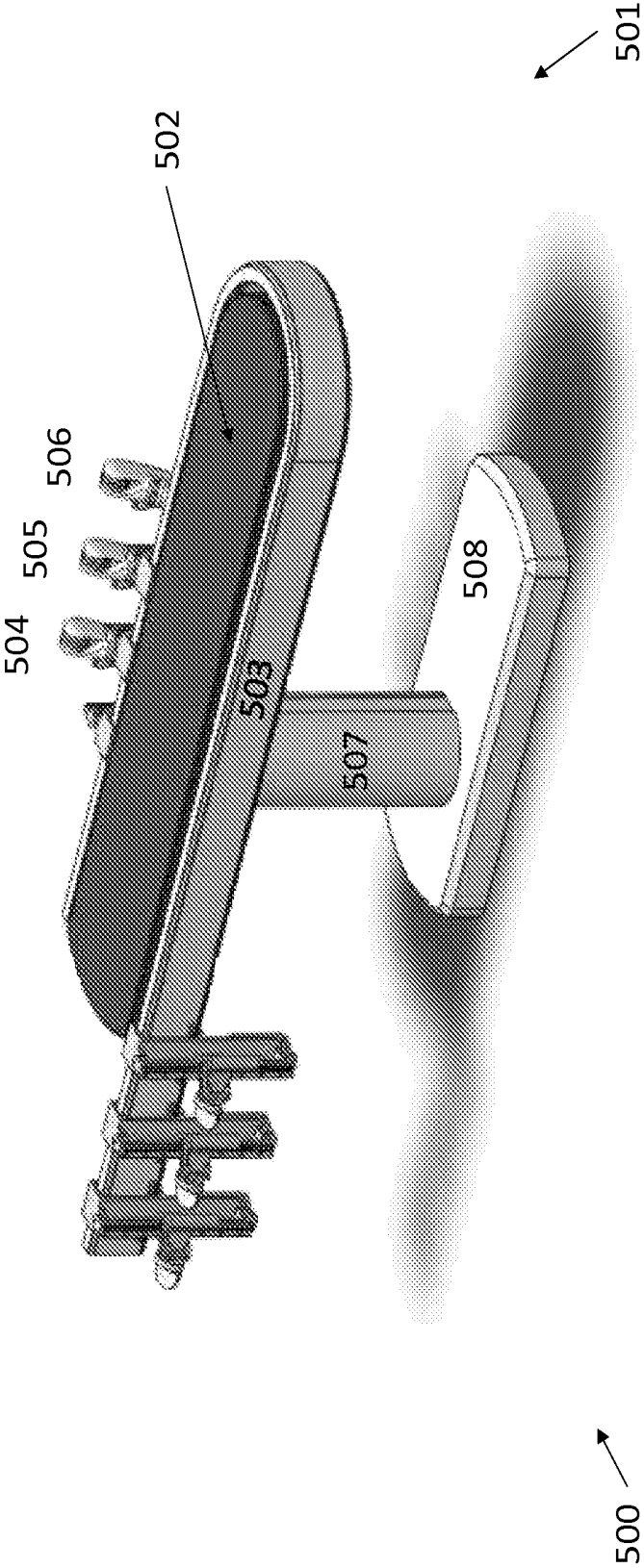


FIG. 5A

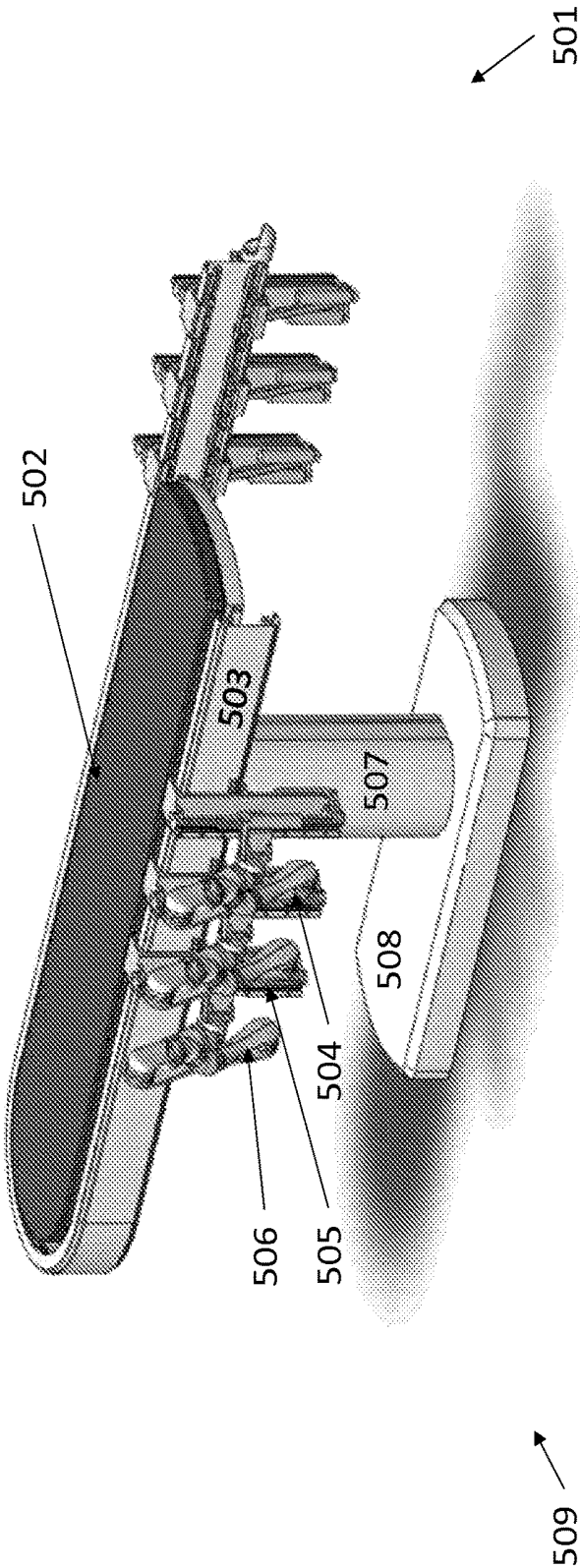


FIG. 5B

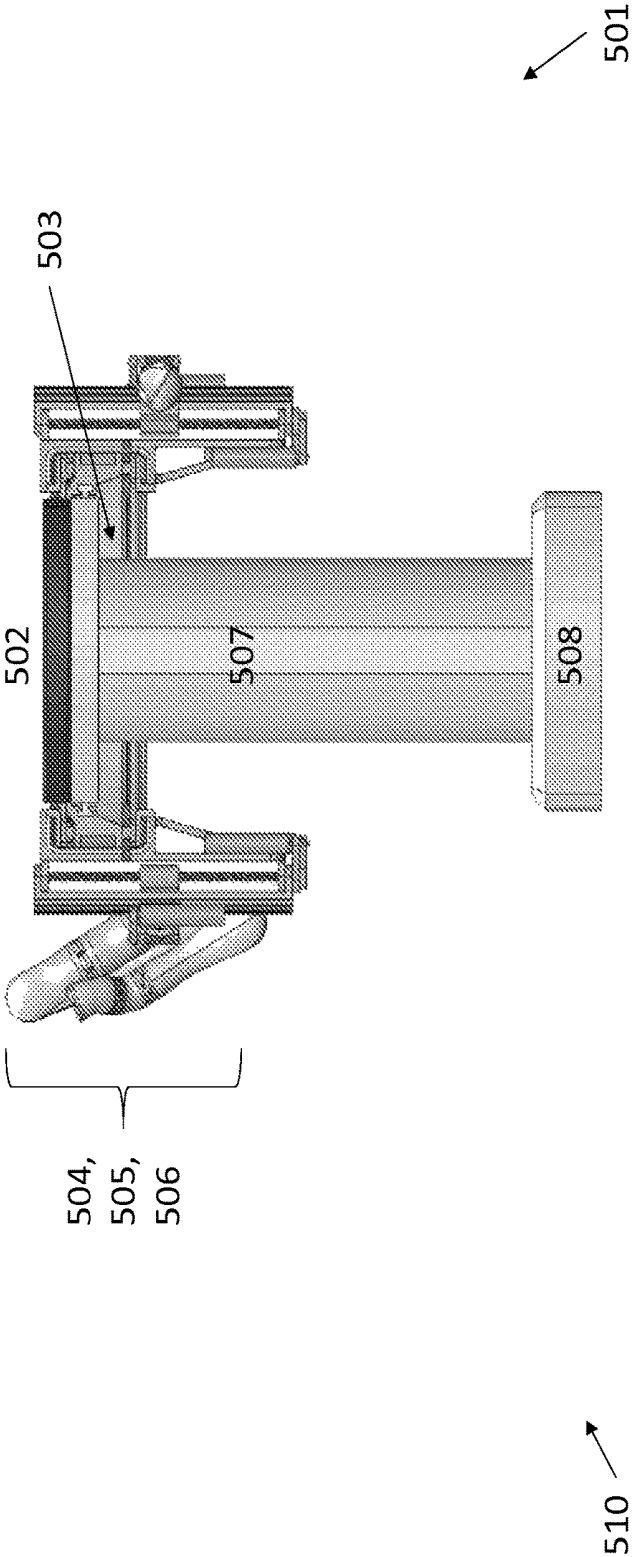
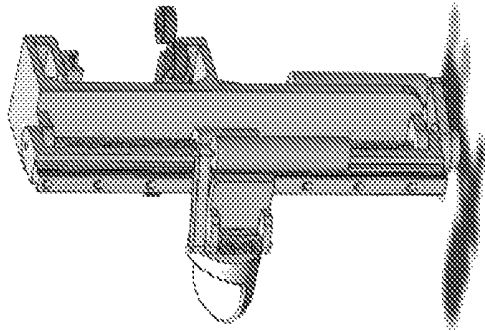
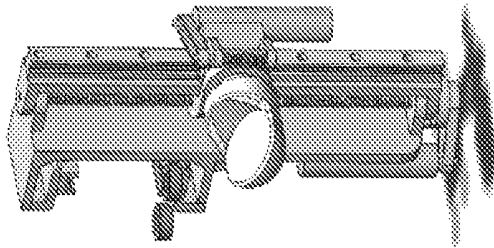


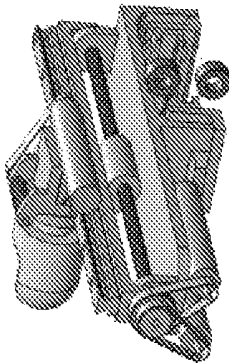
FIG. 5C



513



512



511

FIG. 5D

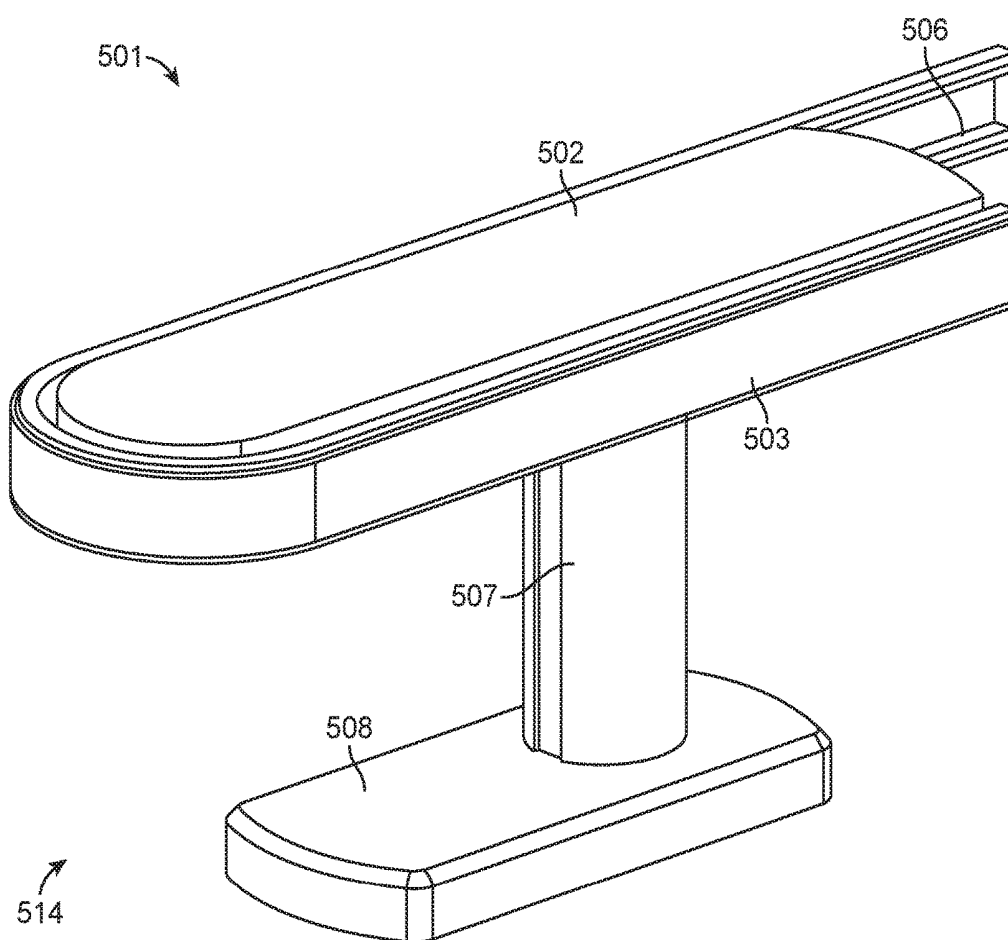


FIG. 5E

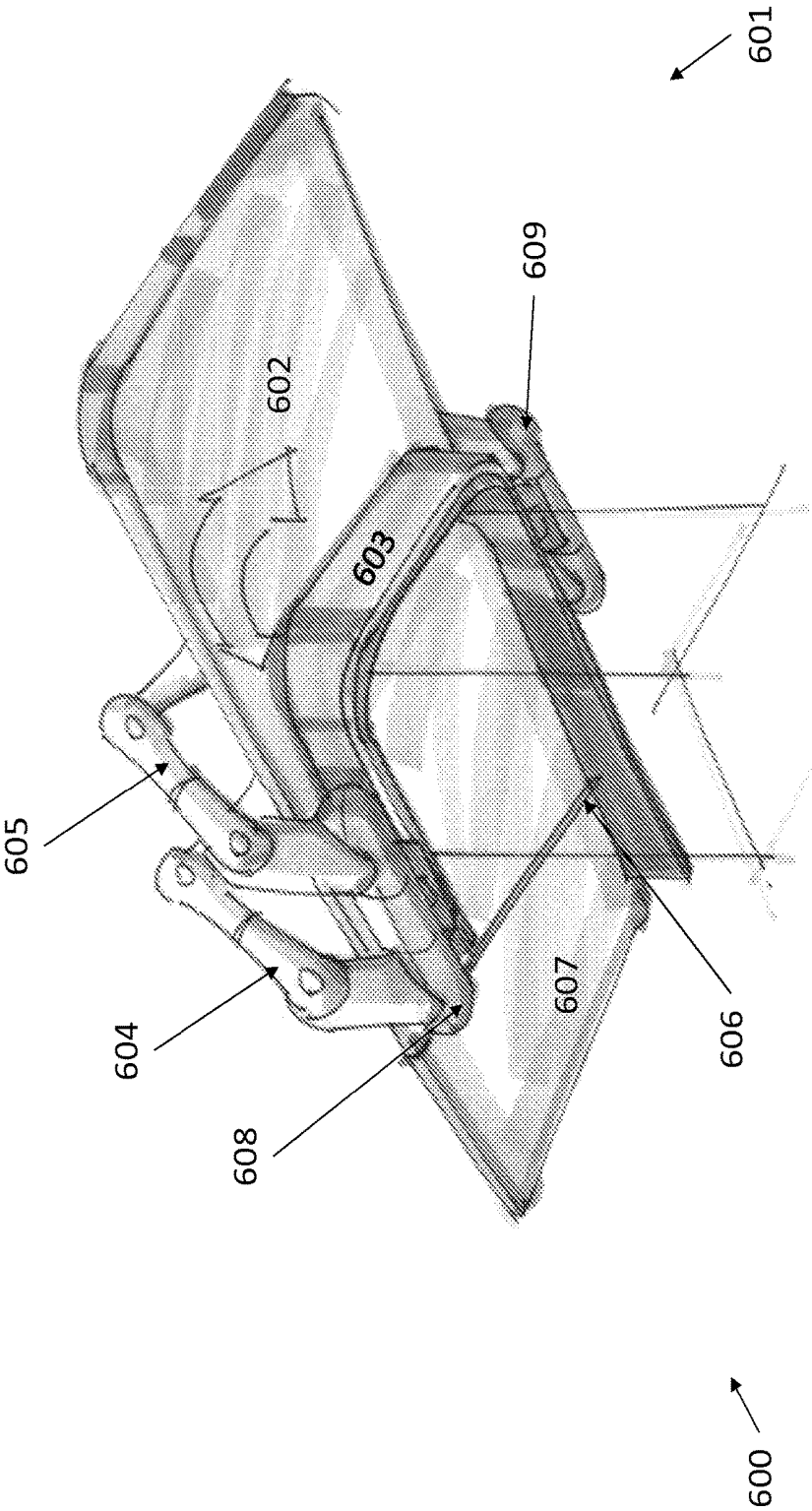
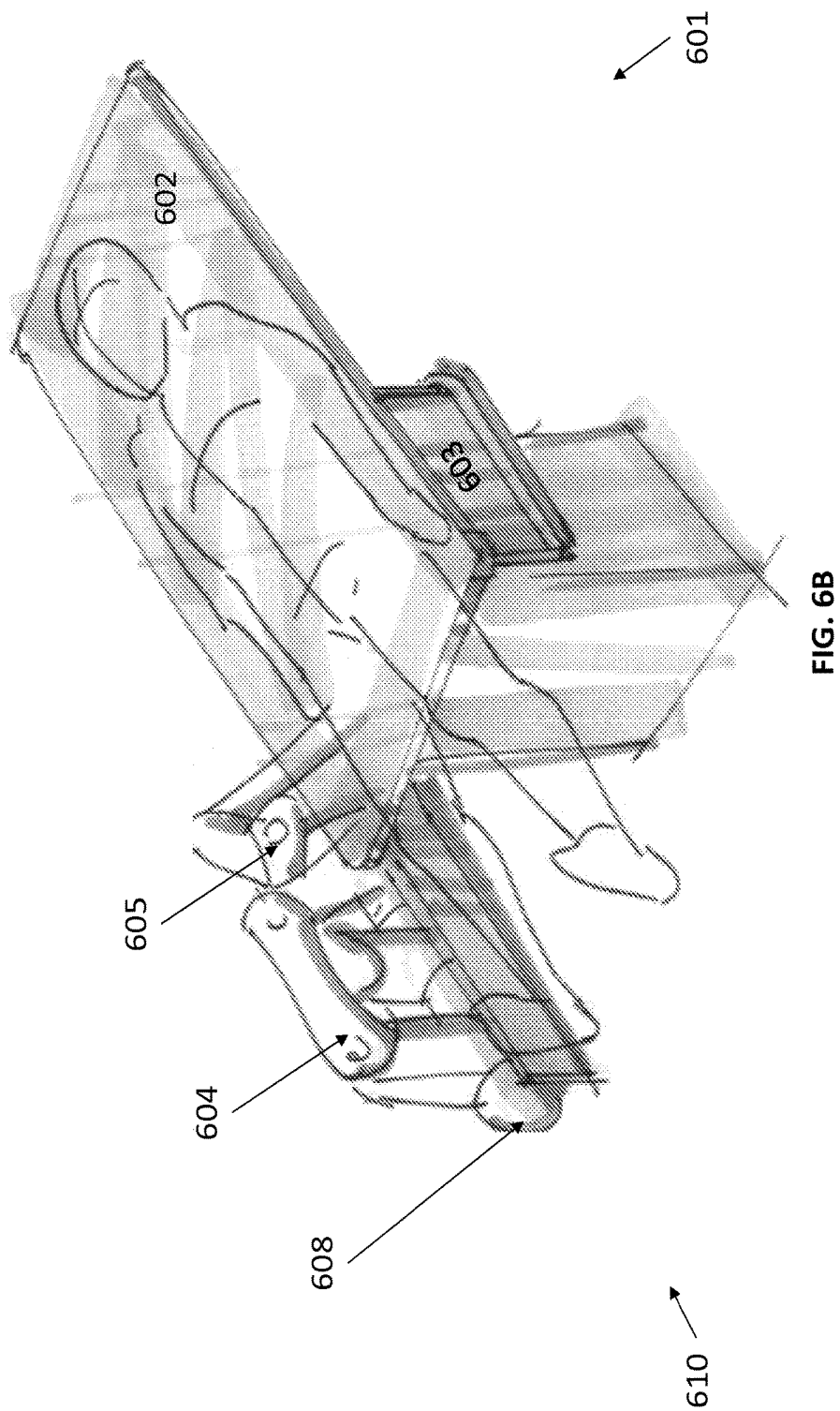


FIG. 6A



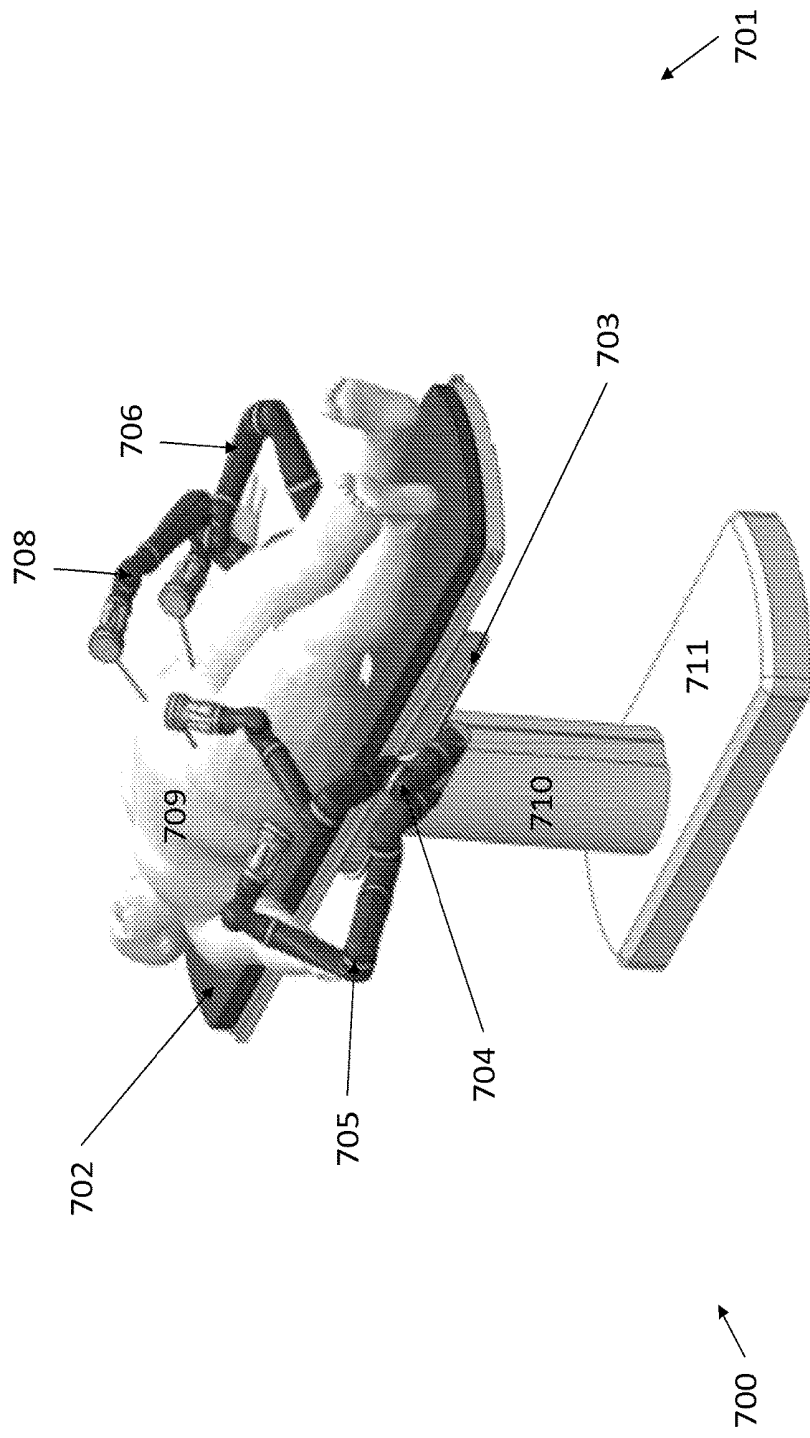


FIG. 7A

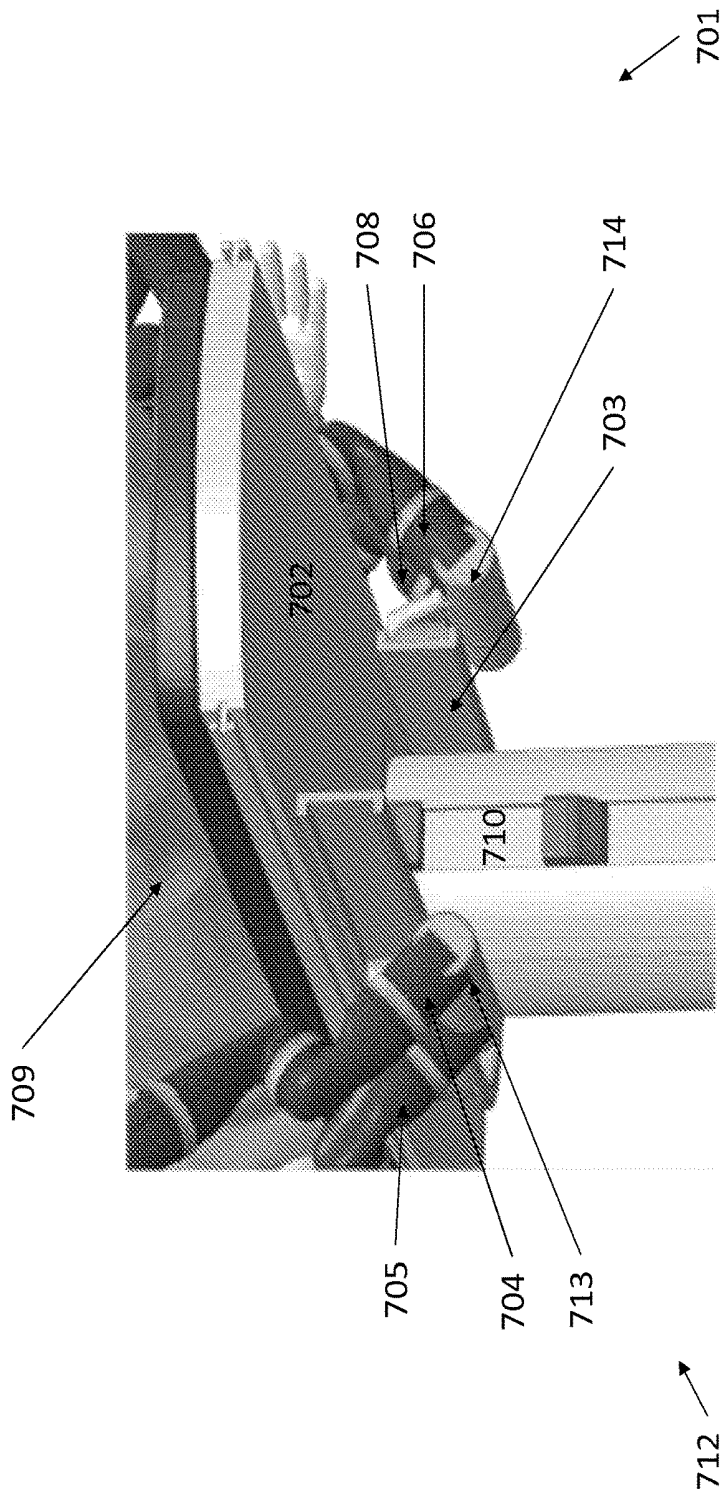


FIG. 7B

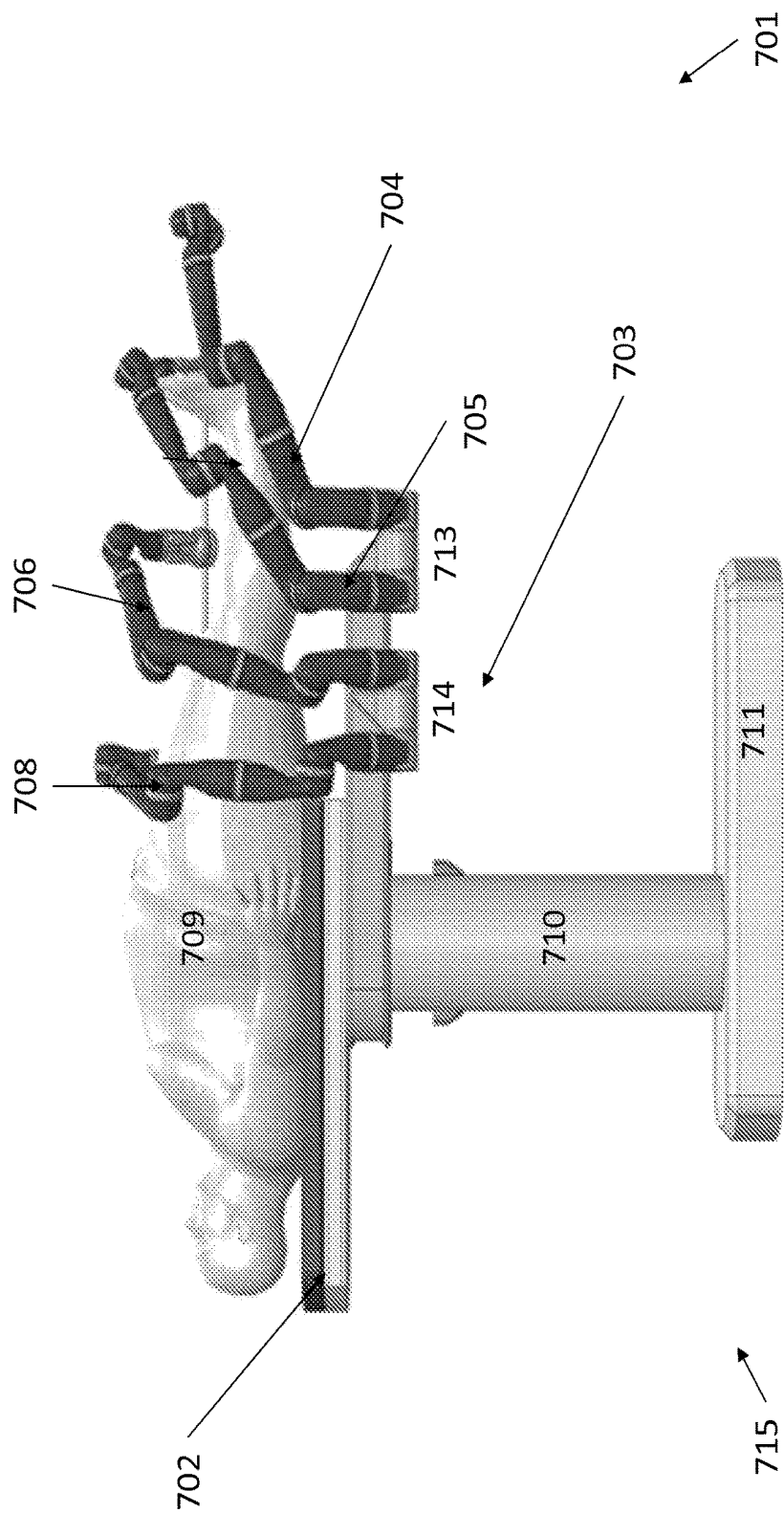


FIG. 7C

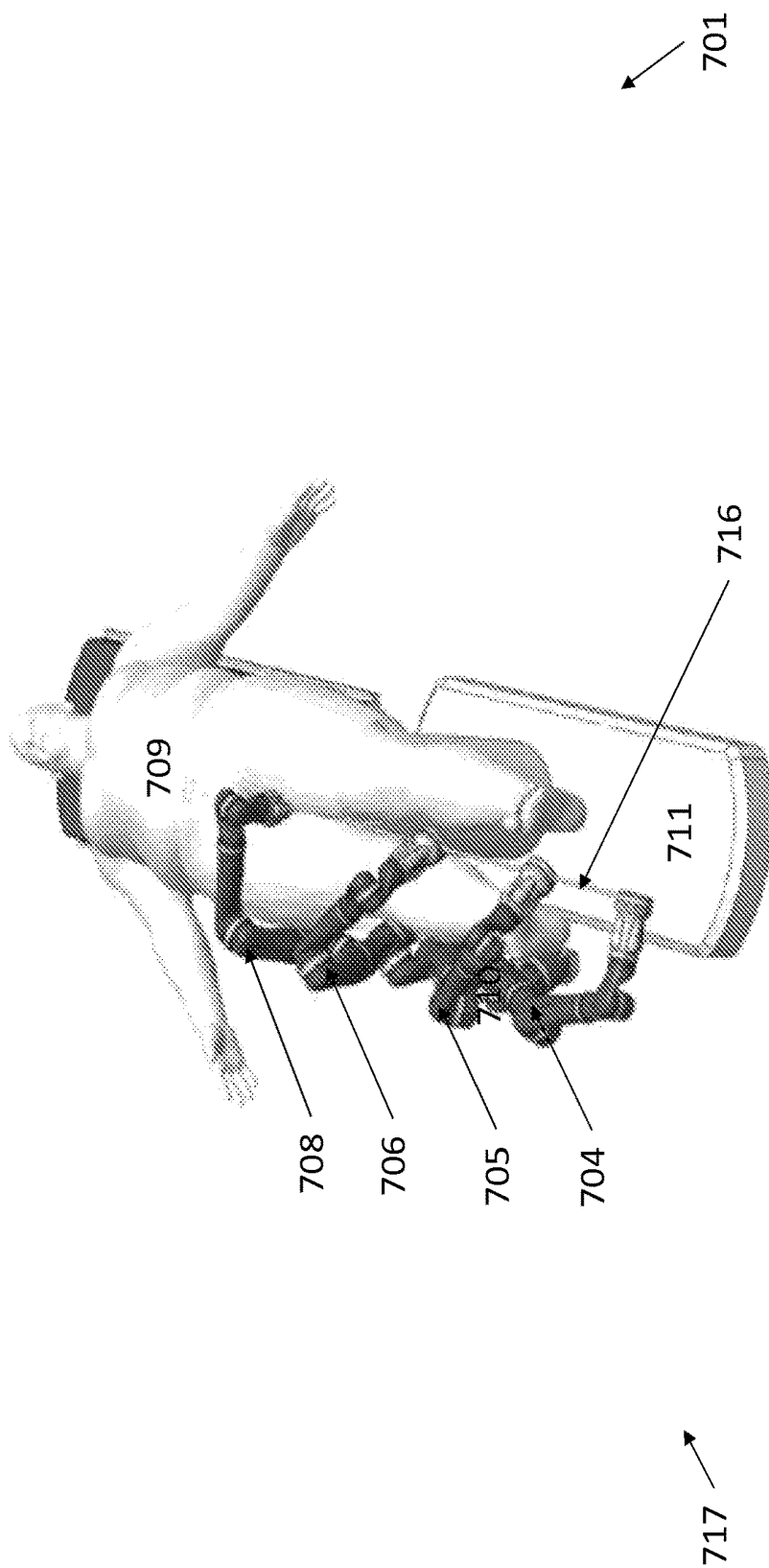


FIG. 7D

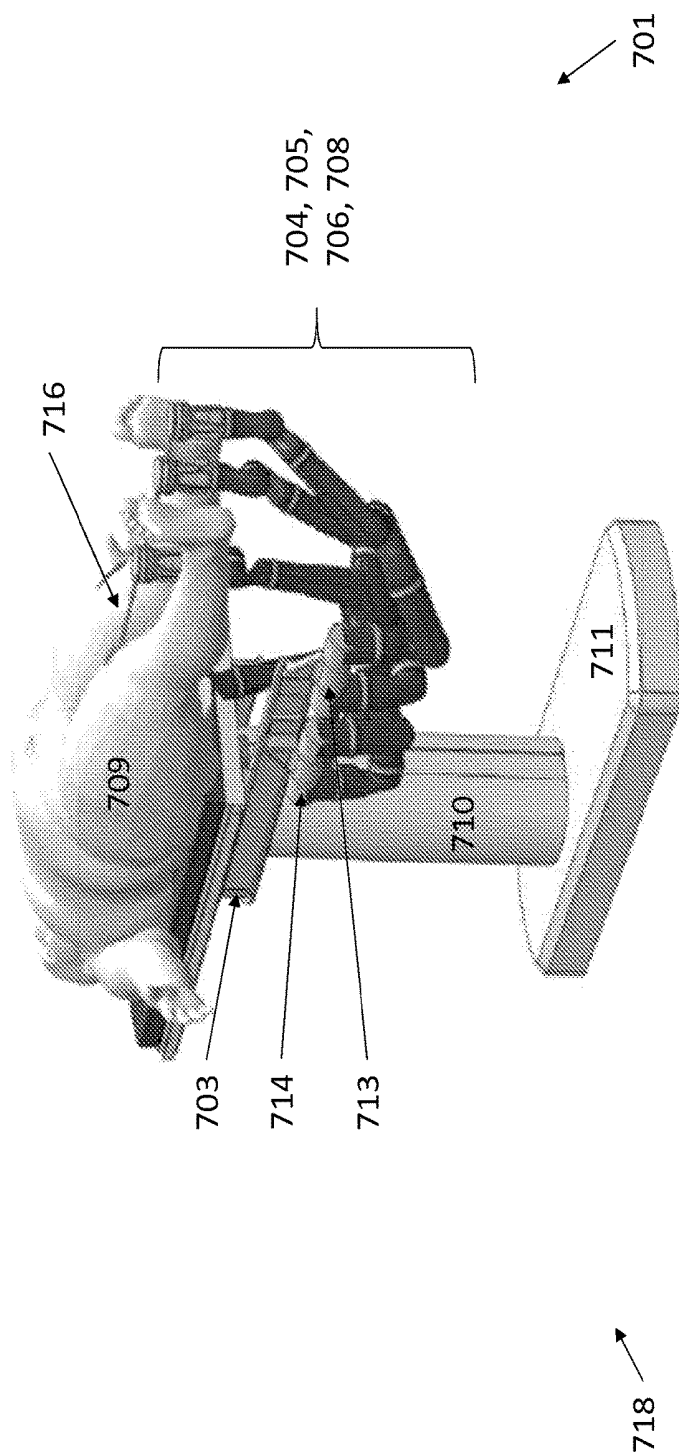


FIG. 7E

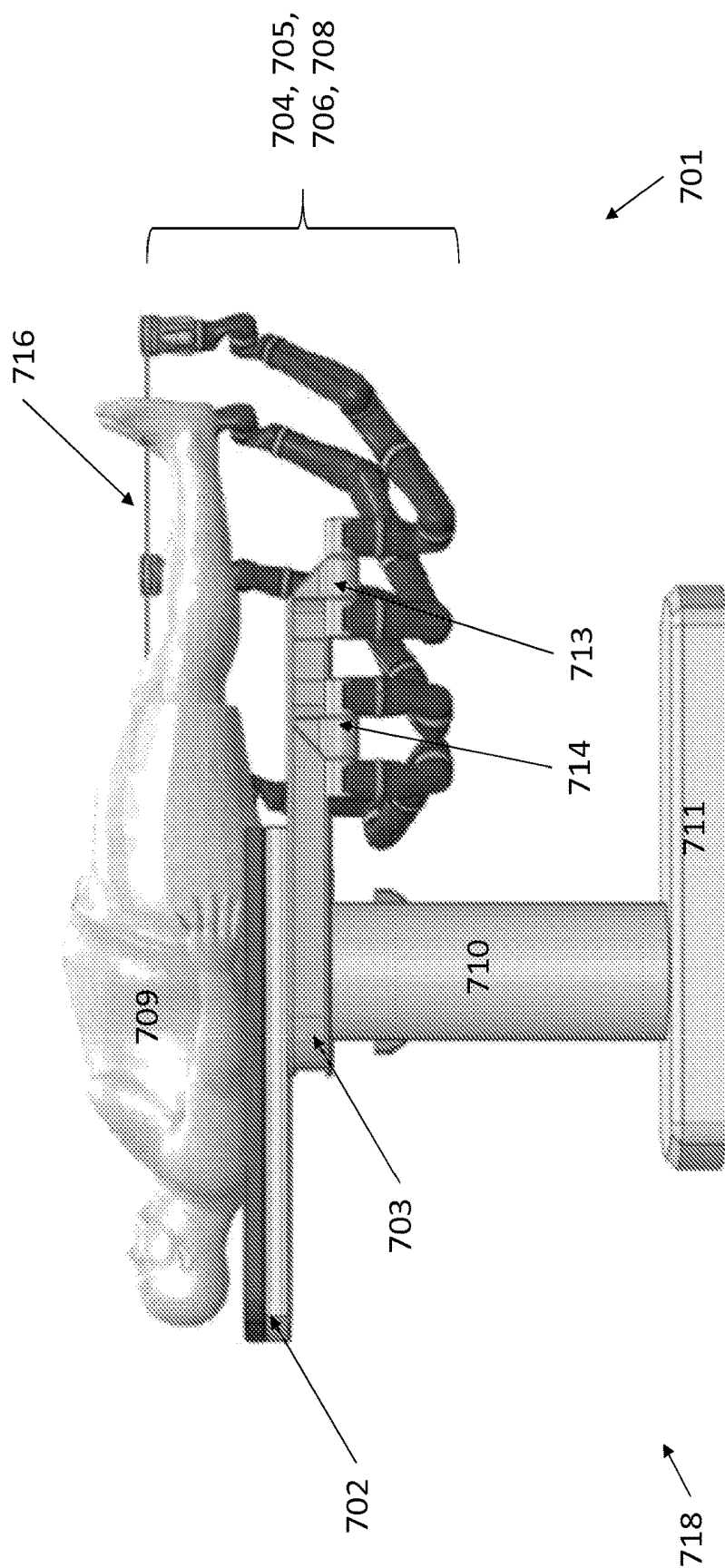
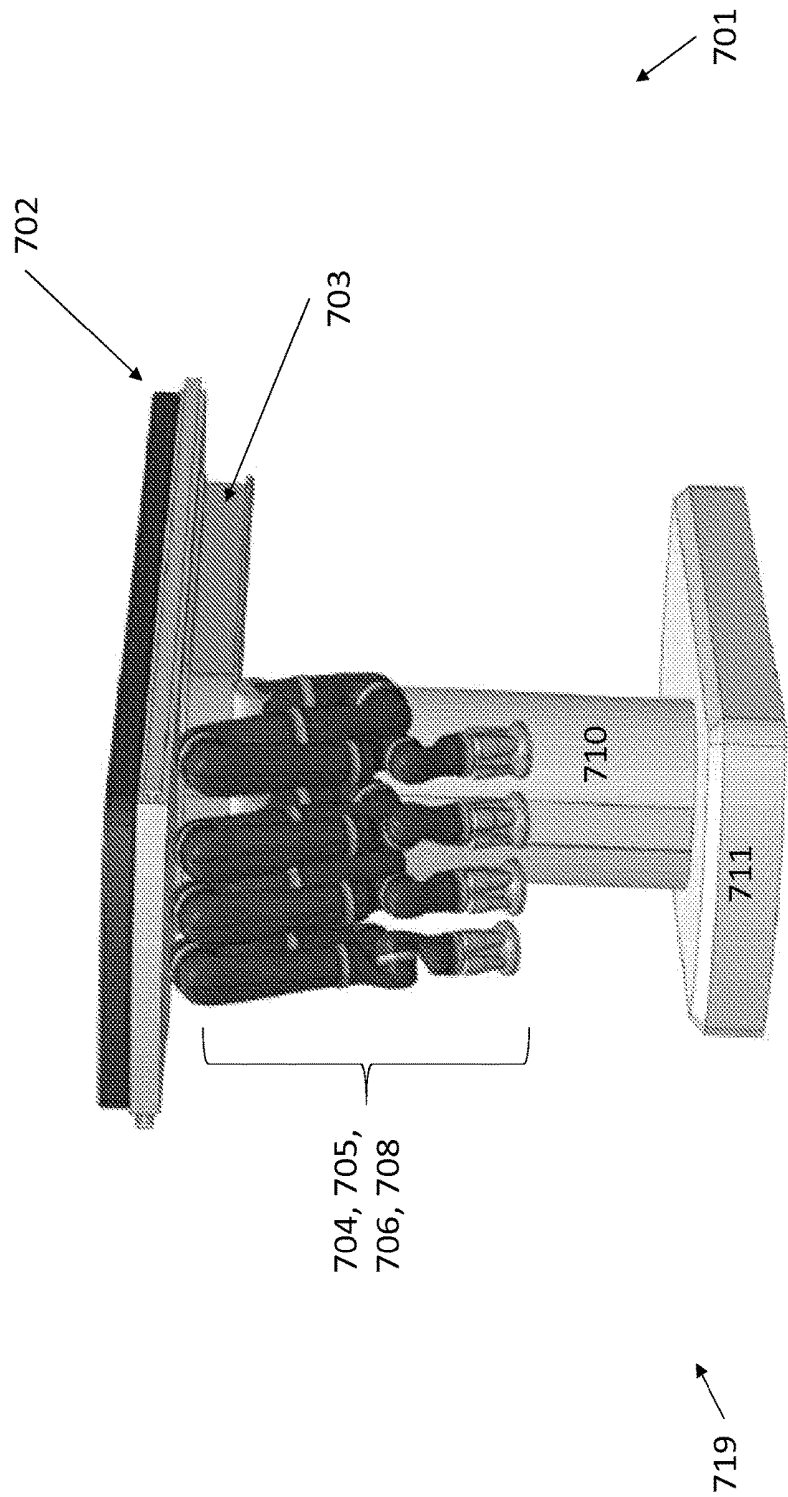


FIG. 7F



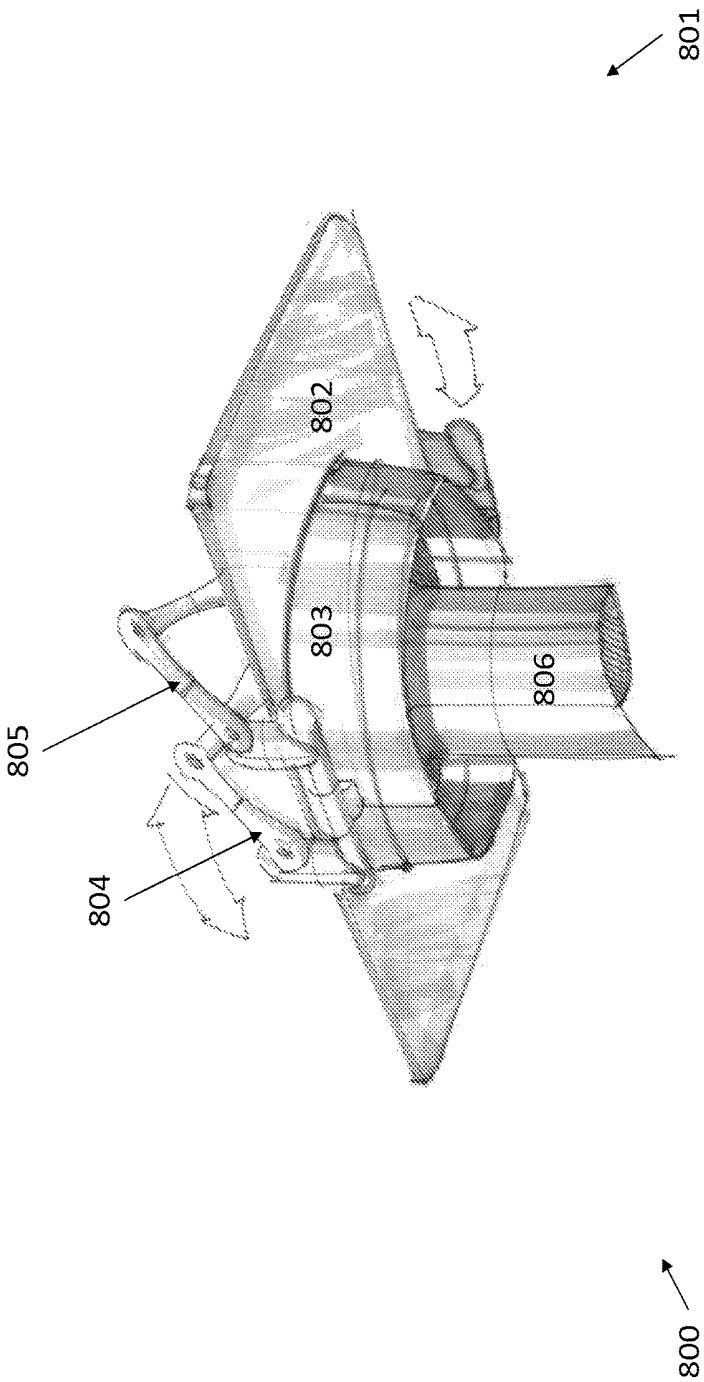


FIG. 8A

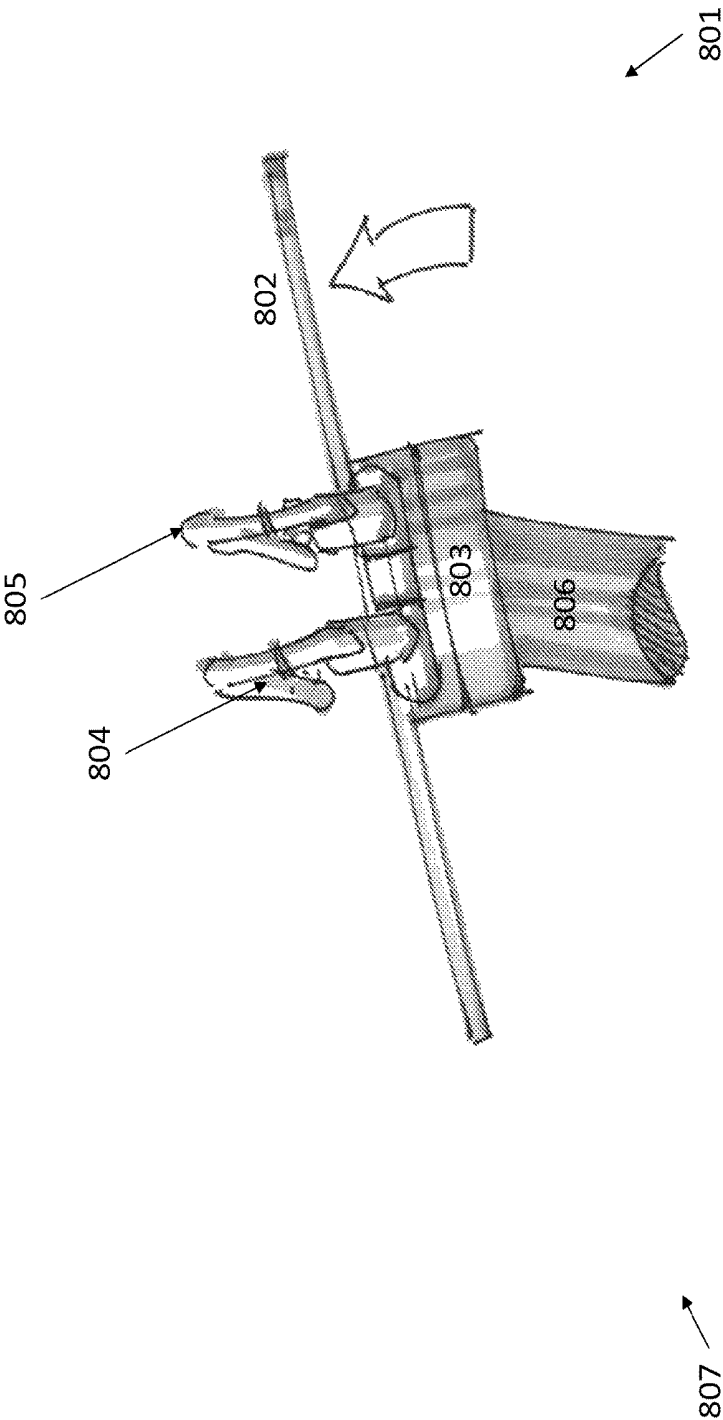


FIG. 8B

1

SURGICAL SYSTEM WITH CONFIGURABLE RAIL-MOUNTED MECHANICAL ARMS

CROSS REFERENCE TO RELATED APPLICATIONS

This application claims the benefit of U.S. Provisional Application No. 62/145,418, filed Apr. 9, 2015, which application is incorporated herein by reference.

The present invention relates to medical instruments, tools, and methods that may be incorporated into a robotic system, such as those disclosed in U.S. patent application Ser. No. 14/523,760, filed Oct. 24, 2014, U.S. Provisional Patent Application No. 62/019,816, filed Jul. 1, 2014, U.S. Provisional Patent Application No. 62/037,520, filed Aug. 14, 2014, and U.S. Provisional Patent Application No. 62/057,936, filed Sep. 30, 2014, the entire contents of which are incorporated herein by reference.

INCORPORATION BY REFERENCE

All publications and patent applications mentioned in this specification are herein incorporated by reference in their entirety to the same extent as if each individual publication or patent application was specifically and individually indicated to be incorporated by reference.

FIELD OF THE INVENTION

The field of the present invention relates to a robotics platform that may be used in a number of surgical procedures. More particularly, the field of the invention pertains to robotic platforms that enable robotically-controlled tools to perform diagnostic and therapeutic surgical procedures.

BACKGROUND OF THE RELATED ART

Use of robotic technologies presents a number of advantages over traditional, manual surgery procedures. In addition to other advantages, robotic surgeries often allow for greater precision, control, and access. Despite these advantages, however, the pre-existing robotics platforms have built-in limitations that are tied to their structural designs and underpinnings. In the absence of a truly flexible system, hospitals and health care practitioners are forced to acquire a variety of robotic systems in order to robotically perform a variety of procedures. The high capital costs, combined with the relatively specialization of the systems, have slowed adoption of robotics platforms for surgery.

Accordingly, there is a need for a robotics platform that is configurable for a number of procedures.

BRIEF SUMMARY OF THE INVENTION

In general, the present invention provides a medical device that comprises a rail having a rounded path, a carriage configured to translate along the rail, the carriage being operatively coupled to the rail, a robotic arm operatively coupled to the carriage, and a horizontal platform proximate to the rail, wherein the robotic arms are configured to perform medical procedures on a patient on the platform. In one aspect, the rounded path is U-shaped. In one aspect, the U-shaped path comprises of a first leg and a second leg, wherein the first leg is longer than the second leg. In another aspect, the rail is configured around a central base. In one aspect, the central base is shaped like a column.

2

In another aspect, a horizontal platform is operatively coupled to the top of the base. In one aspect, the rail is disposed below the platform. In one aspect, the rail is around the platform. In one aspect, the arm is configured to be angled over platform.

In another aspect, the platform is a surgical bed, configured to support the weight of a patient. In one aspect, the surgical bed comprises a first part and a second part, wherein the second part is configured to articulate relative to the first part.

In another aspect, the rail is configured around a horizontal platform. In one aspect, the platform is a surgical bed, configured to support the weight of a patient.

In another aspect, the rounded path is circular. In one aspect, the rail is disposed below the platform. In one aspect, the rail is around the platform.

BRIEF DESCRIPTION OF THE DRAWINGS

The invention will be described, by way of example, and with reference to the accompanying diagrammatic drawings, in which:

FIG. 1 illustrates a surgical bed with an oval track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention;

FIG. 2 illustrates a surgical bed with a U-shaped track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention;

FIG. 3 illustrates an alternative robotics platform to system 201 from FIG. 2;

FIG. 4 illustrates a surgical bed with a rounded track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention;

FIG. 5A illustrates a surgical bed with a rounded track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention;

FIG. 5B illustrates the surgical bed with a rounded track from FIG. 5A, consistent with an embodiment of the present invention;

FIG. 5C illustrates the surgical bed with a rounded track from FIGS. 5A, 5B, consistent with an embodiment of the present invention;

FIG. 5D illustrates several views of carriages for mechanical arms used in system 501 from FIGS. 5A, 5B;

FIG. 5E illustrates the surgical bed with a rounded track from FIG. 5A, consistent with an embodiment of the present invention;

FIGS. 6A and 6B illustrate a surgical bed with a rounded track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention;

FIG. 7A illustrates a surgical bed with a rounded track for robotic arms underneath the edge of the bed, consistent with an embodiment of the present invention;

FIG. 7B illustrates the underside of the surgical bed with a rounded track from FIG. 7A;

FIG. 7C illustrates the surgical bed with a rounded track from FIGS. 7A, 7B;

FIG. 7D illustrates the surgical bed with a rounded track from FIGS. 7A, 7B, 7C;

FIG. 7E illustrates the surgical bed with a rounded track from FIG. 7C;

FIG. 7F illustrates the surgical bed with a rounded track from FIG. 7E;

FIG. 7G illustrates the surgical bed with a rounded track from FIGS. 7A-7F; and

FIGS. 8A and 8B illustrate a surgical bed with a rounded track for robotic arms underneath the edge of the bed, consistent with an embodiment of the present invention.

DETAILED DESCRIPTION OF THE DRAWINGS

Although certain preferred embodiments and examples are disclosed below, inventive subject matter extends beyond the specifically disclosed embodiments to other alternative embodiments and/or uses, and to modifications and equivalents thereof. Thus, the scope of the claims appended hereto is not limited by any of the particular embodiments described below. For example, in any method or process disclosed herein, the acts or operations of the method or process may be performed in any suitable sequence and are not necessarily limited to any particular disclosed sequence. Various operations may be described as multiple discrete operations in turn, in a manner that may be helpful in understanding certain embodiments; however, the order of description should not be construed to imply that these operations are order dependent. Additionally, the structures, systems, and/or devices described herein may be embodied as integrated components or as separate components.

In clinical applications, the design of the base of the robotics platform often constrains the types of procedures that may be performed by the system. For example, in a system where robotic appendages are only available around the abdomen, urology procedures are precluded from being performed. Likewise, robotic arms below the abdomen may not be useful for laparoscopic procedures. Accordingly, the present invention provides a flexible design such that robotic arms may be delivered to multiple access points in a patient around a surgical bed.

FIG. 1 illustrates a surgical bed with an oval track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention. As shown in the isometric view 100 of the robotic system 101, the system 101 comprises of a surgical bed 102, a rail 103 for mechanical arms 104, a support stand 105, and a system base 106. The surgical bed allows for a hinge 107 such that a portion 108 of surgical bed 102 may be declined at a different angle from the rest of the bed. This may be desirable for certain operations, such as when performing a procedure that requires access a patient's lower abdomen, such as ureteroscopy or hysteroscopy.

Encircling the surgical bed 102, the rail 103 provides a structure to slidably translate the mechanical arms 104 to a desired location around the surgical bed 102. The rail 103, which may be referred to as a "track", and the mechanical arms 104 may be slidably translated along it in order to facilitate access for the arms. The rail 103 also provides allows for the conveyance and reception of power, controls, fluidics, aspiration to the mechanical arms 104. The rail 103 may be fully circular and surround all sides of the surgical bed 102.

The mechanical arms 104 may be operatively coupled to the rail 103. The mechanical arms may also be robotic. The translation of the mechanical arms 104 may be actuated either manually or robotically. The mechanical arms 104 may be coupled independently to the rail 103 or in groups via a mechanical carriage that may slide around the rail 103. In addition to providing structural support to the mechanical arms 104, the carriage may be used to convey and receive power, controls, fluidics, and aspiration to and from the arms 104 to the rail 103.

In combination or individually, the support stand 105 and the system base 106 may be used to house electronics, fluidics, pneumatics, and aspiration. The electronics may be used from control, localization, navigation of the arms 104. Thus, as a robotically-driven platform, system 101 provides for a comprehensive surgical bed and tool solution that may be used to perform any number of procedures around a patient.

FIG. 2 illustrates a surgical bed with a U-shaped track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention. As shown in the isometric view 200 of the robotic system 201, the system 201 comprises of a surgical bed 202, a rail 203 for mechanical arms 204, a support stand 205, and a system base 206. Like in system 101, the surgical bed 202 allows for a hinge 207 such that a portion 208 of surgical bed 202 may be declined at a different angle from the rest of the bed 202. As discussed earlier, this may be desirable for certain operations, such as when performing a procedure that requires access a patient's lower abdomen, such as ureteroscopy, hysteroscopy, or colonoscopy.

Running along the surgical bed 202, the rail 203 provides a structure to slidably translate the mechanical arms 204 to a desired location around the surgical bed 202. Unlike rail 103, rail 203 uses a U-shape that enhances access the surgical bed 202. This may provide advantages when position the patient and accessing operative sites on a patient's lower abdomen. The longer leg of the rail 203 allows for the mechanical arms to be aligned to convey a medical instrument into the patient by means of a "virtual rail" such as one discussed in the aforementioned patent applications. As before, the rail 203 may be referred to as a "track", and the mechanical arms 204 may be slidably translated along it in order to facilitate access for the arms. The rail 203 also provides allows for the conveyance and reception of power, controls, fluidics, aspiration to the mechanical arms 204.

In combination or individually, the support stand 205 and the system base 206 may be used to house electronics, fluidics, pneumatics, and aspiration. The electronics may be used from control, localization, navigation of the arms 204. Thus, as a robotically-driven platform, system 201 provides for an improved, comprehensive surgical bed and tool solution that may be used to perform any number of procedures around a patient.

As deployed, the mechanical arms 104 from system 101 and mechanical arms 204 and system 201 are positioned to perform endoluminal procedures to access the access points in the lower abdomen (e.g., urology, ureteroscopy, hysteroscopy, or colonoscopy) and upper abdomen (e.g., bronchoscopy, gastro-intestinal).

FIG. 3 illustrates an alternative robotics platform to system 201 from FIG. 2. As shown in isometric view 300, system 301 incorporates all the technologies disclosed with respect to system 201 with the additional vertical translation apparatus 302 that enables control over the vertical height of the rail 303. System 301 thus allows for vertical translation of the rail 303 relative to the support stand 304.

FIG. 4 illustrates a surgical bed with a rounded track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention. As shown in the isometric view 400 of the robotic system 401, the system 401 comprises of a surgical bed 402, a rail 403 (or "track") for mechanical arms 404, a support stand 405, and a system base 406. The surgical bed 402 may be configured to translate horizontally to position patient 407 relative to mechanical arms 404.

Encircling the surgical bed 402, the rail 403 provides a structure to slidably translate the mechanical arms 404 to a desired location around the surgical bed 402. The rail 403, which may be referred to as a “track”, and the mechanical arms 404 may be slidably translated along it in order to facilitate access for the arms. The rail 403 also provides allows for the conveyance and reception of power, controls, fluidics, aspiration to the mechanical arms 404.

The mechanical arms 404 may be operatively coupled to the rail 403. The mechanical arms 404 may also be robotic. The translation of the mechanical arms 404 may be actuated either manually or robotically. The mechanical arms 404 may be coupled independently to the rail 403 or in groups via a mechanical carriage that may slide around the rail 403. In addition to providing structural support to the mechanical arms 404, the carriage may be used to convey and receive power, controls, fluidics, and aspiration to and from the arms 404 to the rail 403. The ability to translate the arms 404 and translate the bed 402 allows for nearly unlimited access to different portions of the anatomy of patient 407.

In combination or individually, the support stand 405 and the system base 406 may be used to house electronics, fluidics, pneumatics, and aspiration. The electronics may be used from control, localization, navigation of the arms 404. Thus, as a robotically-driven platform, system 401 provides for a comprehensive surgical bed and tool solution that may be used to perform any number of procedures around a patient. The support stand 405 may also translate vertically, allowing for easier access to the patient 407 and operative site.

As deployed in view 400, mechanical arms 404 may be positioned to access the abdomen of patient 407 for laparoscopic procedures.

FIG. 5A illustrates a surgical bed with a rounded track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention. As shown in the isometric view 500 of the robotic system 501, the system 501 comprises of a surgical bed 502, a rail 503 (or “track”) for mechanical arms 504, 505, 506, a support stand 507, and a system base 508. The surgical bed 502 may be configured to translate horizontally to position a patient relative to mechanical arms 504, 505, 506.

Encircling the surgical bed 502, the rail 503 provides a structure to slidably translate the mechanical arms 504, 505, 506 to a desired location around the surgical bed 502. The rail 503, which may be referred to as a “track”, and the mechanical arms 504, 505, 506 may be slidably translated along it in order to facilitate access for the arms 504, 505, 506. The rail 503 also provides allows for the conveyance and reception of power, controls, fluidics, aspiration to the mechanical arms 504, 505, 506.

The mechanical arms 504, 505, 506 may be operatively coupled to the rail 503. The mechanical arms 504, 505, 506 may also be robotic. The translation of the mechanical arms 504, 505, 506 may be actuated either manually or robotically. The mechanical arms 504, 505, 506 may be coupled independently to the rail 503 or individually or in groups via mechanical carriages that may slide around the rail 503. In addition to providing structural support to the mechanical arms 504, 505, 506 a carriage may be used to convey and receive power, controls, fluidics, and aspiration to and from the arms 504, 505, 506 to the rail 503. The ability to translate the arms 504, 505, 506 and translate the bed 502 allows for nearly unlimited access to different portions of the anatomy of a patient.

In combination or individually, the support stand 507 and the system base 508 may be used to house electronics,

fluidics, pneumatics, and aspiration. The electronics may be used from control, localization, navigation of the arms 504, 505, 506. Thus, as a robotically-driven platform, system 501 provides for a comprehensive surgical bed and tool solution that may be used to perform any number of procedures around a patient. The support stand 507 may also translate vertically, allowing for easier access to the patient and operative site.

As deployed in view 500, mechanical arms 504, 505, 506 may be positioned to access the abdomen of patient for laparoscopic procedures, while the carriages on the other side of rail 503 may be positioned to hold mechanical arms to create a virtual rail for access points in the lower abdomen (e.g., urology, ureteroscopy, or hysteroscopy).

FIG. 5B illustrates the surgical bed with a rounded track from FIG. 5A, consistent with an embodiment of the present invention. Reverse isometric view 509 provides a different perspective of the robotic system 501, surgical bed 502, rail 503 (or “track”) for mechanical arms 504, 505, 506 a support stand 507, and a system base 508.

FIG. 5C illustrates the surgical bed with a rounded track from FIGS. 5A, 5B, consistent with an embodiment of the present invention. Rear view 510 provides a different perspective of the robotic system 501, surgical bed 502, rail 503 (or “track”) for mechanical arms 504, 505, 506, support stand 507, and a system base 508.

FIG. 5D illustrates several views of carriages for mechanical arms used in system 501 from FIGS. 5A, 5B, 5C, consistent with an embodiment of the present invention. Side views 511, 512, 513 provide different perspectives on a mechanically-driven carriage in system 501.

FIG. 5E illustrates the surgical bed with a rounded track from FIG. 5A, consistent with an embodiment of the present invention. View 514 provides a different perspective of the robotic system 501, surgical bed 502, rail 503 (or “track”), support stand 507, and system base 508, absent mechanical arms 504, 505, 506.

FIG. 6A illustrates a surgical bed with a rounded track for robotic arms along the edge of the bed, consistent with an embodiment of the present invention. As shown in the view 600, the system 601 comprises of a surgical bed 602, a rail 603 (or “track”) for mechanical arms 604, 605. The surgical bed 602 may be configured to translate horizontally to position a patient relative to mechanical arms 604, 605. The surgical bed 602 allows for a hinge 606 such that a portion 607 of surgical bed 602 may be declined at a different angle from the rest of the bed 602. As discussed earlier, this may be desirable for certain operations, such as when performing a procedure that requires access a patient’s lower abdomen, such as ureteroscopy, hysteroscopy, or colonoscopy.

Underneath the surgical bed 602, the rail 603 provides a structure to slidably translate the mechanical arms 604, 605 to a desired location around the surgical bed 602. The rail 603, which may be referred to as a “track”, and the mechanical arms 604, 605 may be slidably translated along it in order to facilitate access for the arms 604, 605. The rail 603 also provides allows for the conveyance and reception of power, controls, fluidics, aspiration to the mechanical arms 604, 605. As shown in FIG. 6A, there may be a shorter leg and longer leg portion of the U-shape rail 603. In some embodiments, the rail 603 may be fully circular, rather than a U-shaped.

The mechanical arms 604, 605 may be operatively coupled to the rail 603. The mechanical arms 604, 605 may also be robotic. The translation of the mechanical arms 604, 605 may be actuated either manually or robotically. The mechanical arms 604, 605 may be coupled independently to

the rail 603 or individually or in groups (as shown) via a mechanical carriage 608 that may slide around the rail 603. In addition to providing structural support to the mechanical arms 604, 605, the carriage 606 may be used to convey and receive power, controls, fluidics, and aspiration to and from the arms 604, 605 to the rail 603. The ability to translate the arms 604, 605 and translate the bed 602 allows for nearly unlimited access to different portions of the anatomy of a patient.

Not shown, system 601 may also incorporate a support stand and the system base to house electronics, fluidics, pneumatics, and aspiration. The electronics may be used from control, localization, navigation of the arms 604, 605. Thus, as a robotically-driven platform, system 601 provides for a comprehensive surgical bed and tool solution that may be used to perform any number of procedures around a patient. The support stand may also translate vertically, allowing for easier access to the patient and operative site. The support stand may also support vertical translation of the rail 603 in order to facilitate access to particular anatomical access points.

As deployed in view 600, mechanical arms 604, 605 on carriage 608 may be positioned to access the abdomen of patient for procedures, such as laparoscopy or endoscopy, while a carriage 609 on the other side of rail 603 may be positioned to hold additional mechanical arms.

FIG. 6B illustrates the surgical bed with a rounded track from FIG. 6A. As shown in the view 610, mechanical arms 604, 605 on carriage 608 may be slidably translated to the long side of the rail 603. View 610 also provides a view of a support base. As deployed in view 610, mechanical arms 604, 605 on carriage 608 may be positioned to form a virtual rail for access to the anatomical lumens in the lower abdomen for various procedures, such as ureteroscopy, hysteroscopy, or colonoscopy. To facilitate access surgical bed 602 has been slidably translated forwards from the rail 603.

FIG. 7A illustrates a surgical bed with a rounded track for robotic arms underneath the edge of the bed, consistent with an embodiment of the present invention. As shown in the view 700, the system 701 comprises of a surgical bed 702, a rail 703 (or "track") for mechanical arms 704, 705, 706, 708. The surgical bed 702 may be configured to translate horizontally to position patient 709 relative to mechanical arms 704, 705, 706, 708. The surgical bed 702 may include a hinge such that the lower portion of surgical bed 702 may be declined at a different angle from the rest of the bed 702. As discussed earlier, this may be desirable for certain operations, such as when performing a procedure that requires access a patient's lower abdomen, such as ureteroscopy, hysteroscopy, or colonoscopy.

Underneath the surgical bed 702, the rail 703 provides a structure to slidably translate the mechanical arms 704, 705, 706, 708 to a desired location around the surgical bed 702. The rail 703, which may be referred to as a "track" and the mechanical arms 704, 705 may be slidably translated along it in order to facilitate access for the arms 704, 705, 706, 708. The rail 703 also provides allows for the conveyance and reception of power, controls, fluidics, aspiration to the mechanical arms 704, 705, 706, 708.

The mechanical arms 704, 705, 706, 708 may be operatively coupled to the rail 703. The mechanical arms 704, 705, 706, 708 may also be robotic. The translation of the mechanical arms 704, 705, 706, 708 may be actuated either manually or robotically. The mechanical arms 704, 705, 706, 708 may be coupled independently to the rail 703 or individually or in groups via a mechanical carriage that may slide around the rail 703. In addition to providing structural

support to the mechanical arms 704, 705, 706, 708, the carriage may be used to convey and receive power, controls, fluidics, and aspiration to and from the arms 704, 705, 706, 708 to the rail 703. The ability to translate the arms 704, 705, 706, 708 and translate the bed 702 allows for nearly unlimited access to different portions of the anatomy of a patient.

System 701 may also incorporate support stand 710 and system base 711 to house electronics, fluidics, pneumatics, and aspiration. The electronics may be used from control, localization, navigation of the arms 704, 705, 706, 708. Thus, as a robotically-driven platform, system 701 provides for a comprehensive surgical bed and tool solution that may be used to perform any number of procedures around a patient. The rail 703 on support stand 710 may also translate vertically, allowing for easier access to the patient and operative site. The support stand may also telescope.

As deployed in view 700, mechanical arms 704, 705, 706, 708 may be positioned to access the abdomen of patient 709 for laparoscopic procedures, using a variety of rigid or semi-rigid laparoscopic instruments.

FIG. 7B illustrates the underside of the surgical bed with a rounded track from FIG. 7A. As shown in the view 712, mechanical arms 704, 705, 706, 708 may be coupled to the rail 703 using carriages 713 and 714, which may be slidably translated along rail 703. Carriages 713 and 714 may be oriented at various angles from rail 703 to provide an additional access to the patient 709. View 712 also provides a view of a support base 709 which shows structures to vertically translate rail 703 and bed 702.

FIG. 7C illustrates the surgical bed with a rounded track from FIGS. 7A, 7B. As shown in side view 715, carriages 713 and 714 may be positioned along rail 703 such that mechanical arms 704, 705, 706, 708 may be arranged to form a virtual rail to guide an endoscopic device 716 into an anatomical lumen in the lower abdomen of patient 709 for a procedure such as ureteroscopy, hysteroscopy, or colonoscopy.

FIG. 7D illustrates the surgical bed with a rounded track from FIGS. 7A, 7B, 7C. Top view 717 provides a different perspective of the positioning of mechanical arms 704, 705, 706, 708 to form a virtual rail to guide an endoscopic device 716 into an anatomical lumen in the lower abdomen of patient 709 for a procedure such as ureteroscopy, hysteroscopy, or colonoscopy.

FIG. 7E illustrates the surgical bed with a rounded track from FIG. 7C. Isometric view 718 provides an alternative positioning of mechanical arms 704, 705, 706, 708 to form a virtual rail to guide an endoscopic device 714 into an anatomical lumen in the lower abdomen of patient 709 for a procedure such as ureteroscopy, hysteroscopy, or colonoscopy. In view 717, the carriages 713 and 714 may be oriented below rail 703 to position mechanical arms 704, 705, 706, 708 such that the virtual rail is positioned lower than shown in FIGS. 7C and 7D.

FIG. 7F illustrates the surgical bed with a rounded track from FIG. 7E. Side view 719 provides a different perspective of the positioning of carriages 713 and 714 such that mechanical arms 704, 705, 706, 708 form a virtual rail to guide an endoscopic device 716 into an anatomical lumen in the lower abdomen of patient 709 for a procedure such as ureteroscopy, hysteroscopy, or colonoscopy.

FIG. 7G illustrates the surgical bed with a rounded track from FIGS. 7A-7F. View 719 shows stowage of mechanical arms 704, 705, 706, 708 through positioning of carriages 713 and 714 together along rail 703 under surgical bed 702.

FIGS. 8A and 8B illustrate a surgical bed with a rounded track for robotic arms underneath the edge of the bed,

consistent with an embodiment of the present invention. As shown in the view **800**, the system **801** comprises of a surgical bed **802**, a rail **803** (or “track”) for mechanical arms, such as **804**, **805**. The surgical bed **802** may be configured to translate horizontally to position a patient relative to the mechanical arms. As shown in view **807** from FIG. **8B**, the surgical bed **802** may tilted on the support stand **806** to improve physician access to the patient.

Underneath the surgical bed **802**, the rail **803** provides a structure to slidingly translate the mechanical arms **804**, **805** to a desired location around the surgical bed **802**. The rail **803**, which may be referred to as a “track”, and the mechanical arms **804**, **805** may be slidingly translated along it in order to facilitate access for the arms. The rail **803** also provides allows for the conveyance and reception of power, controls, fluidics, aspiration to the mechanical arms.

The mechanical arms may be operatively coupled to the rail **803**. The mechanical arms may also be robotic. The translation of the mechanical arms **804**, **805** may be actuated either manually or robotically. The mechanical arms **804**, **805** may be coupled independently to the rail **803** or individually or in groups via a mechanical carriage that may slide around the rail **803**. In addition to providing structural support to the mechanical arms **804**, **805** the carriage may be used to convey and receive power, controls, fluidics, aspiration to and from the arms **804**, **805** to the support base **806**. The ability to translate the arms **804**, **805** and translate the bed **802** allows for nearly unlimited access to different portions of the anatomy of a patient.

System **801** may also incorporate support stand **806** to house electronics, fluidics, pneumatics, and aspiration. The electronics may be used from control, localization, navigation of the arms **804**, **805**. Thus, as a robotically-driven platform, system **801** provides for a comprehensive surgical bed and tool solution that may be used to perform any number of procedures around a patient. The rail **803** on support stand **806** may also translate vertically, allowing for easier access to the patient and operative site. The support stand may also telescope.

As deployed in view **800**, mechanical arms **804**, **805** may be positioned to access the abdomen of a patient for laparoscopic procedures, using a variety of rigid or semi-rigid laparoscopic instruments.

The aforementioned embodiments of the present invention may be designed to interface with robotics instrument device manipulators, tools, hardware, and software such as those disclosed in the aforementioned patent applications that are incorporated by reference. For example, the embodiments in this specification may be configured to be driven by an instrument drive mechanism or an instrument device manipulator that is attached to the distal end of a robotic arm through a sterile interface, such as a drape. As part of a larger robotics system, robotic control signals may be communicated from a remotely-located user interface, down the robotic arm, and to the instrument device manipulator to control the instrument or tool.

For purposes of comparing various embodiments, certain aspects and advantages of these embodiments are described. Not necessarily all such aspects or advantages are achieved by any particular embodiment. Thus, for example, various embodiments may be carried out in a manner that achieves or optimizes one advantage or group of advantages as taught herein without necessarily achieving other aspects or advantages as may also be taught or suggested herein.

Elements or components shown with any embodiment herein are exemplary for the specific embodiment and may be used on or in combination with other embodiments

disclosed herein. While the invention is susceptible to various modifications and alternative forms, specific examples thereof have been shown in the drawings and are herein described in detail. The invention is not limited, however, to the particular forms or methods disclosed, but to the contrary, covers all modifications, equivalents and alternatives thereof.

What is claimed is:

1. A medical device comprising:

a horizontal platform having a first lateral side, a second lateral side opposite the first lateral side, a top end, and a bottom end opposite the top end;

a first linear rail portion extending along the first lateral side of the horizontal platform;

a second linear rail portion extending along the second lateral side of the horizontal platform and toward and beyond the bottom end of the horizontal platform;

a carriage configured to translate along the second linear rail portion, the carriage being operatively coupled to the second linear rail portion; and

a robotic arm operatively coupled to the carriage, wherein the robotic arm is configured to be moved about the horizontal platform by the carriage to perform a medical procedure on a patient on the horizontal platform, and

wherein the entirety of the carriage is configured to be moved beyond the bottom end of the horizontal platform along the second linear rail portion parallel to the second lateral side.

2. The medical device of claim 1, wherein a connecting section connects the first linear rail portion and the second linear rail portion.

3. The medical device of claim 2, wherein the first linear rail portion, the second linear rail portion, and the connection section form a rail path, wherein the rail path is U-shaped.

4. The medical device of claim 1, wherein the horizontal platform comprises an upper surface and a lower surface, wherein the upper surface is configured to support the patient thereon, and wherein the carriage and the robotic arm are positioned beneath the upper surface of the horizontal platform.

5. The medical device of claim 1, further comprising additional robotic arms, wherein at least one robotic arm of the additional robotic arms is continuously movable between the first and second lateral sides of the horizontal platform.

6. The medical device of claim 1, further comprising a central base, wherein the rail is positioned around the central base.

7. The medical device of claim 6, wherein the central base is shaped like a column.

8. The medical device of claim 6, wherein the horizontal platform is operatively coupled to the top of the central base.

9. The medical device of claim 6, wherein the horizontal platform is configured to one or more of translate horizontally relative to the central base, translate vertically relative to the central base, tilt relative to the central base, or rotate relative to the central base.

10. The medical device of claim 9, wherein the central base comprises a support stand for the horizontal platform, and wherein the support stand is configured to vertically translate to translate the horizontal platform vertically relative to the central base.

11. The medical device of claim 1, wherein the rail is disposed around the horizontal platform.

12. The medical device of claim 1, wherein the robotic arm is configured to be angled over the horizontal platform.

13. The medical device of claim 1, wherein the horizontal platform comprises a surgical bed, configured to support the weight of a patient.

14. The medical device of claim 1, further comprising additional robotic arms, wherein the additional robotic arms are configured to be delivered to a plurality of access points in the patient around the horizontal platform. 5

15. The medical device of claim 1, further comprising additional carriages configured to translate along the second linear rail portion. 10

16. The medical device of claim 15, wherein each individual robotic arm is operatively coupled to a corresponding individual carriage.

17. The medical device of claim 1, wherein the second linear rail portion includes a distal-most end that extends beyond the bottom end of the horizontal platform. 15

18. The medical device of claim 1, wherein the robotic arm is configured to hold one or more tools for performing a ureteroscopy or hysteroscopy.

19. The medical device of claim 1, wherein the first linear rail portion is aligned with the second linear rail portion along a first length of the second linear rail portion, and wherein the first linear rail portion is not aligned with the second rail portion along a second length of the second linear rail portion. 20
25

* * * * *

专利名称(译)	具有可配置轨道安装机械臂的手术系统		
公开(公告)号	US10159533	公开(公告)日	2018-12-25
申请号	US15/094179	申请日	2016-04-08
[标]申请(专利权)人(译)	AURIS手术机器人技术		
申请(专利权)人(译)	AURIS手术机器人, INC.		
[标]发明人	MOLL FREDERIC YU ALAN		
发明人	MOLL, FREDERIC YU, ALAN		
IPC分类号	A61B17/00 A61G13/04 A61G13/10 A61B34/30 A61G13/06 A61B90/57		
CPC分类号	A61B34/30 A61G13/04 A61G13/06 A61G13/10 A61G13/101 A61B2034/304 A61B2090/571		
优先权	62/145418 2015-04-09 US		
其他公开文献	US20160296294A1		
外部链接	Espacenet		

摘要(译)

一种机器人手术系统，包括用于支撑患者的水平平台，围绕水平平台定位的轨道，可操作地连接到并配置成沿着轨道平移的托架，以及可操作地连接到托架并且通过所述托架围绕患者平移的机械臂。机械臂配置成在由平移托架提供的各种位置对患者进行操作。导轨为托架提供圆形路径，例如U形路径。U形路径可包括第一腿和第二腿，第一腿比第二腿长。此外，该系统可包括可操作地连接到轨道的多个托架和多个机械臂。而且，该系统还可包括中央底座，水平平台可相对于中央底座铰接，例如通过水平或垂直平移，旋转或倾斜。

