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Sholev(10) **Pub. No.: US 2008/0091066 A1**(43) **Pub. Date: Apr. 17, 2008**(54) **CAMERA HOLDER DEVICE AND METHOD THEREOF****Publication Classification**(75) Inventor: **Mordehai Sholev, Amikam (IL)**(51) **Int. Cl.****A61B 1/04** (2006.01)(52) **U.S. Cl.** **600/112**

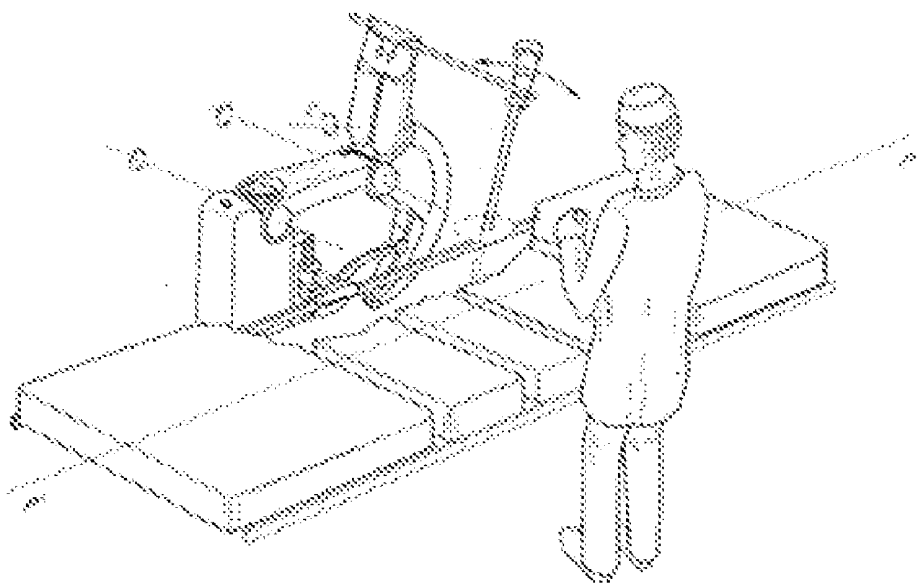
Correspondence Address:

FLEIT KAIN GIBBONS GUTMAN BONGINI & BIANCO**21355 EAST DIXIE HIGHWAY****SUITE 115****MIAMI, FL 33180 (US)**(73) Assignee: **M.S.T. MEDICAL SURGERY TECHNOLOGIES LTD., NAZERETH (IL)**(21) Appl. No.: **11/874,576**(22) Filed: **Oct. 18, 2007****Related U.S. Application Data**

(63) Continuation of application No. PCT/IL2006/000478, filed on Apr. 20, 2006.

(57) **ABSTRACT**

An improved interface between the surgeon and an endoscope system for laparoscopic surgery, holding a laparoscopic came and/or controlling an automated endoscope assistant includes at least one wireless transmitter with at least one operating key (12a), at least one wireless receiver (11), at least one conventional laparoscopy computerized system (15) loaded with conventional surgical instrument spatial location software, and conventional automated assistant maneuvering software, software loaded onto to the conventional laparoscopy system that enables a visual response to the depression of at least one key on the wireless transmitter as well as an interface with the conventional automated assistant maneuvering software so as to achieve movement of the endoscope, and at least one video screen (30).



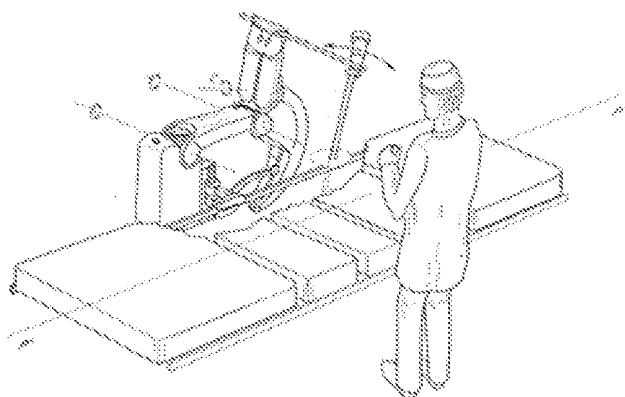


Fig. 1a

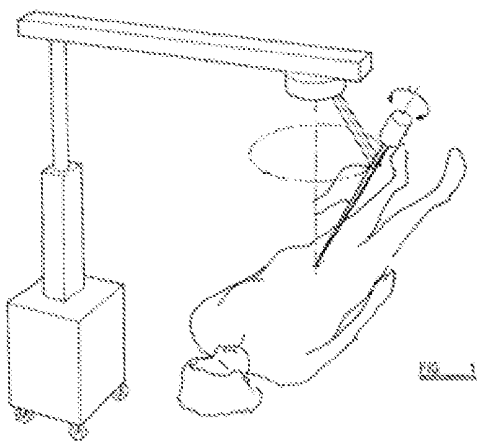


Fig. 1c

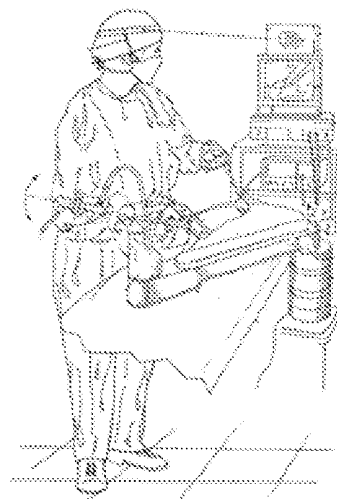


Fig. 1b

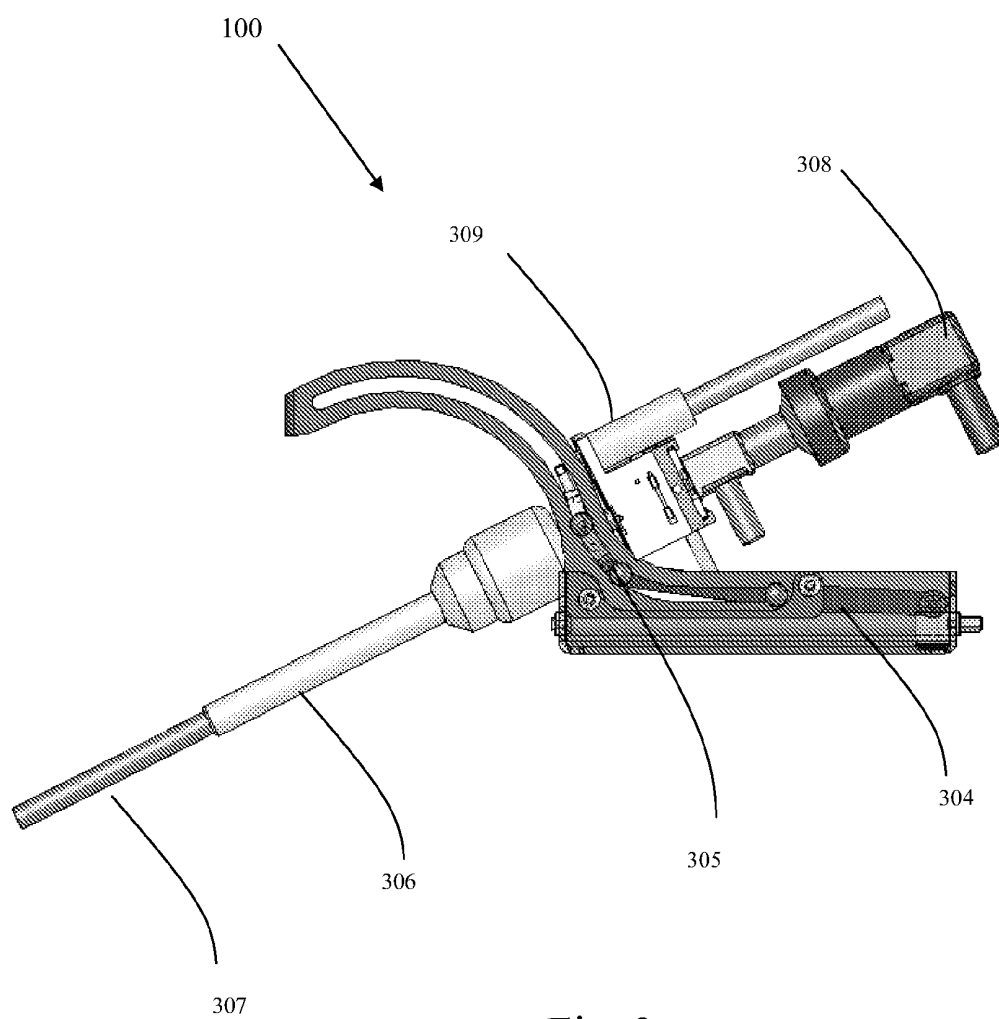


Fig. 2

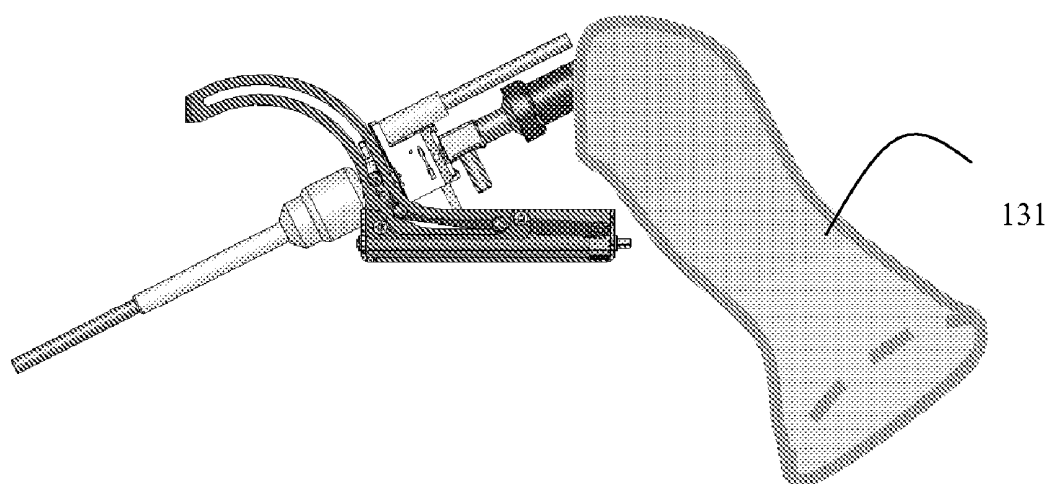


Fig. 3a

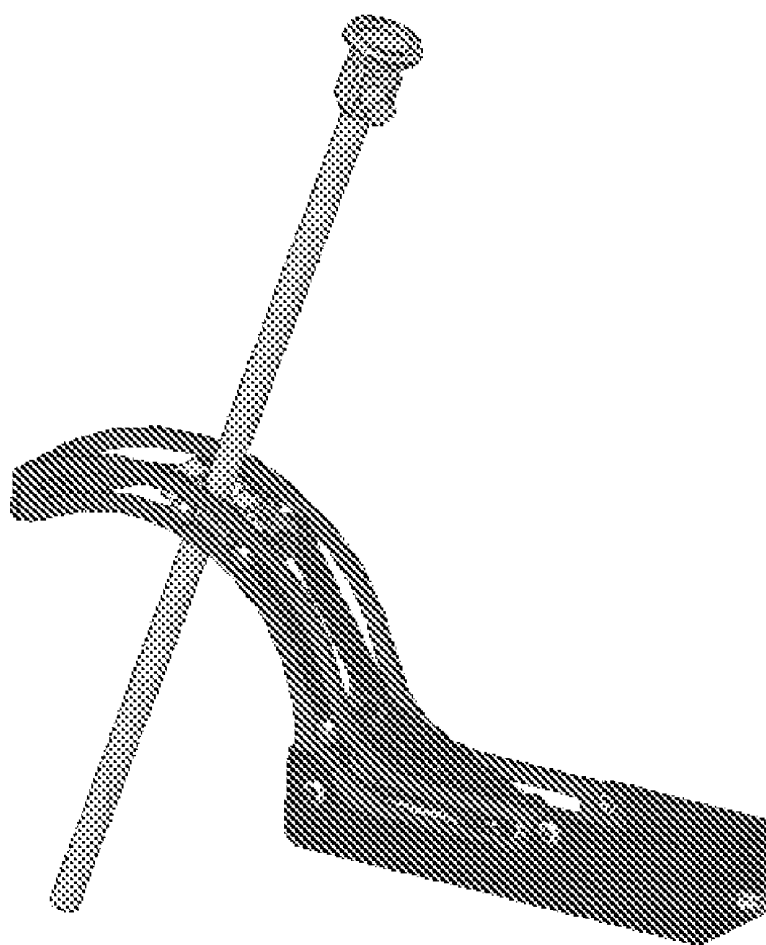


Fig. 36

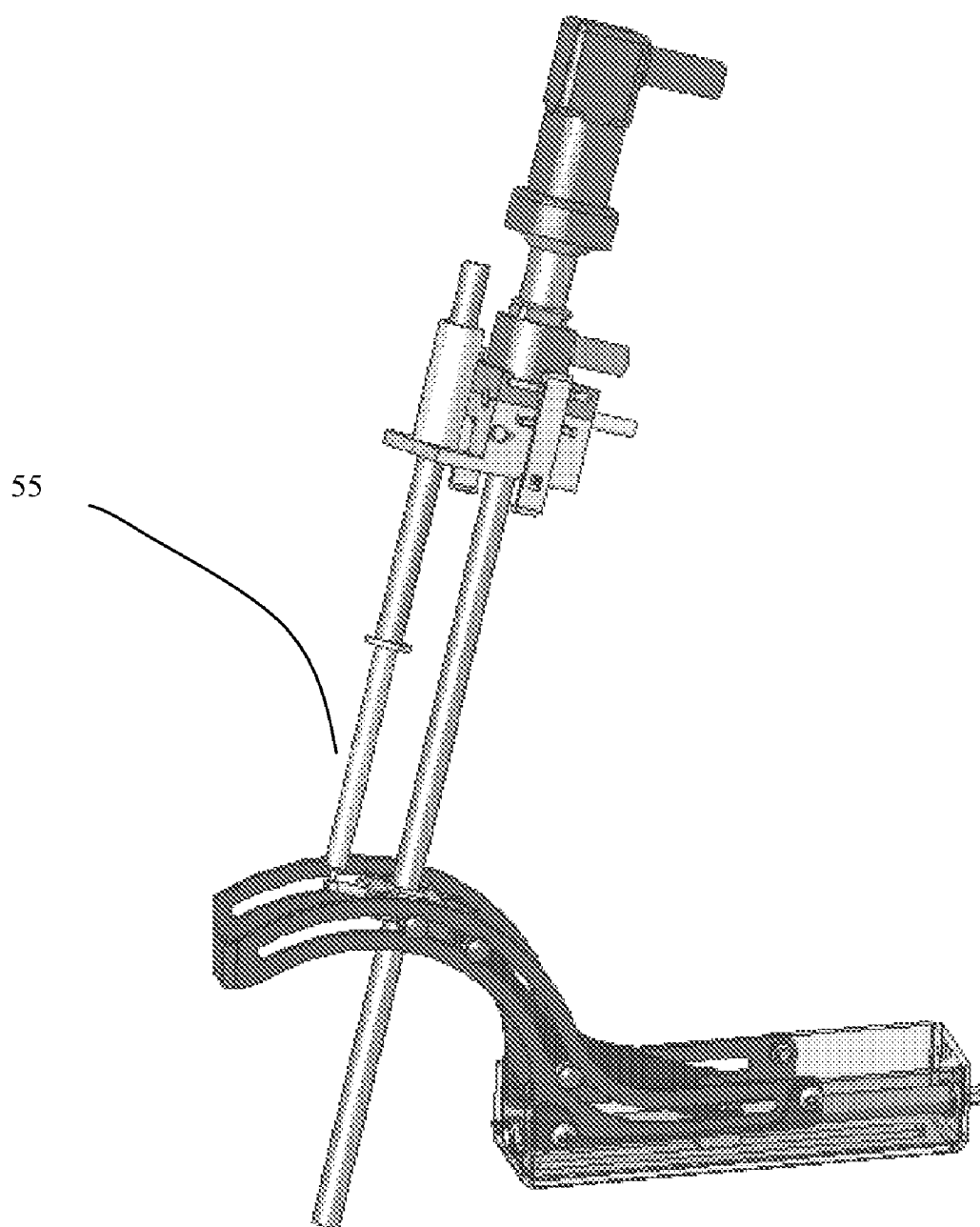


Fig. 3c

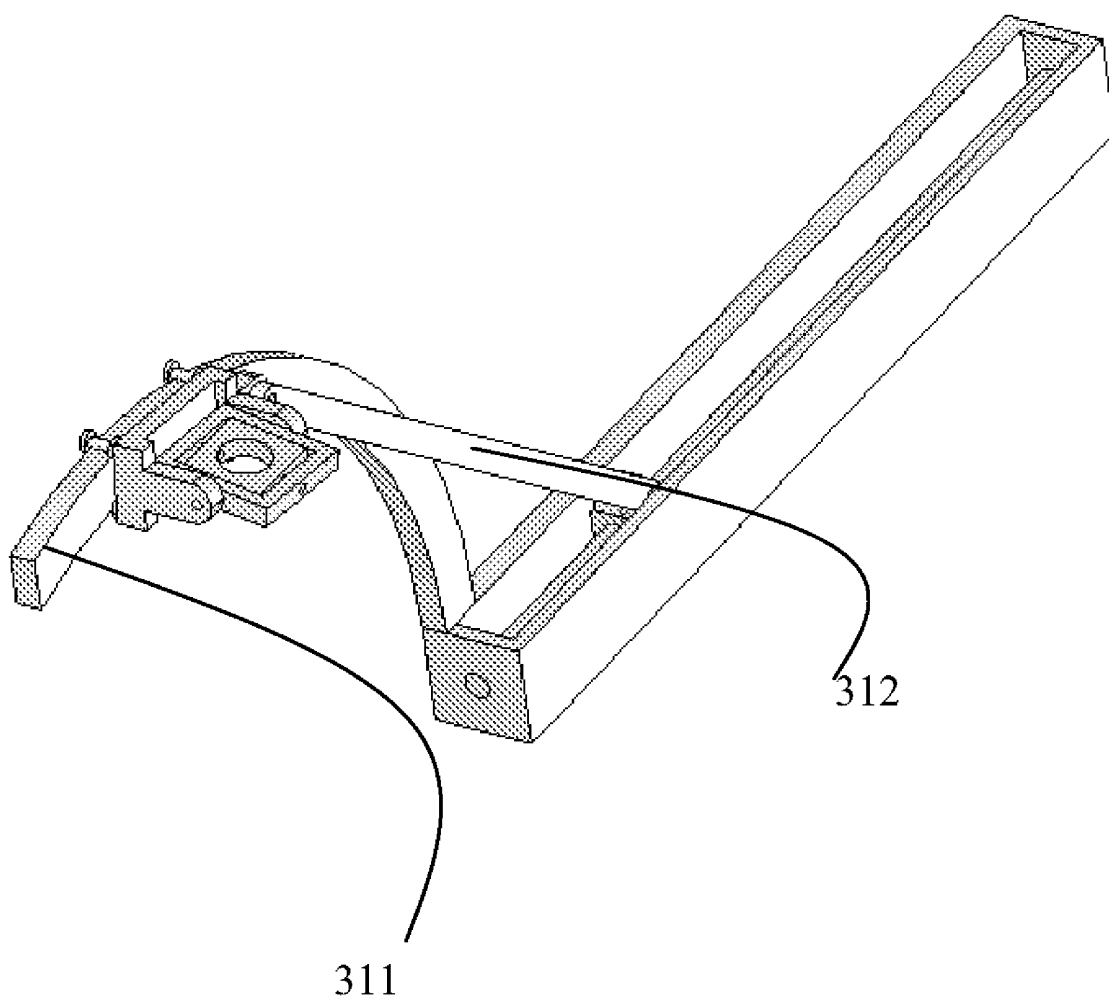


Fig. 4

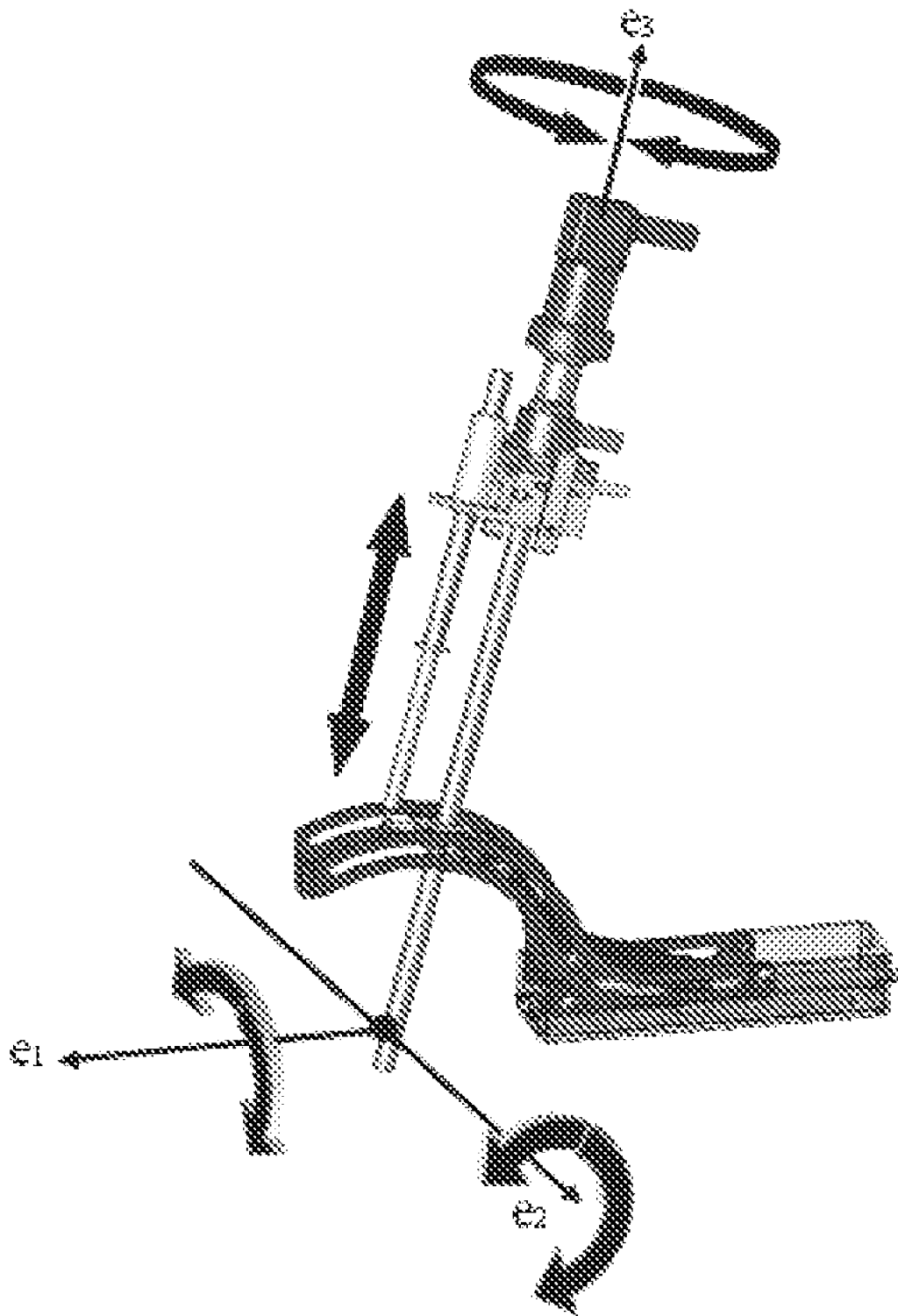


Fig. 5

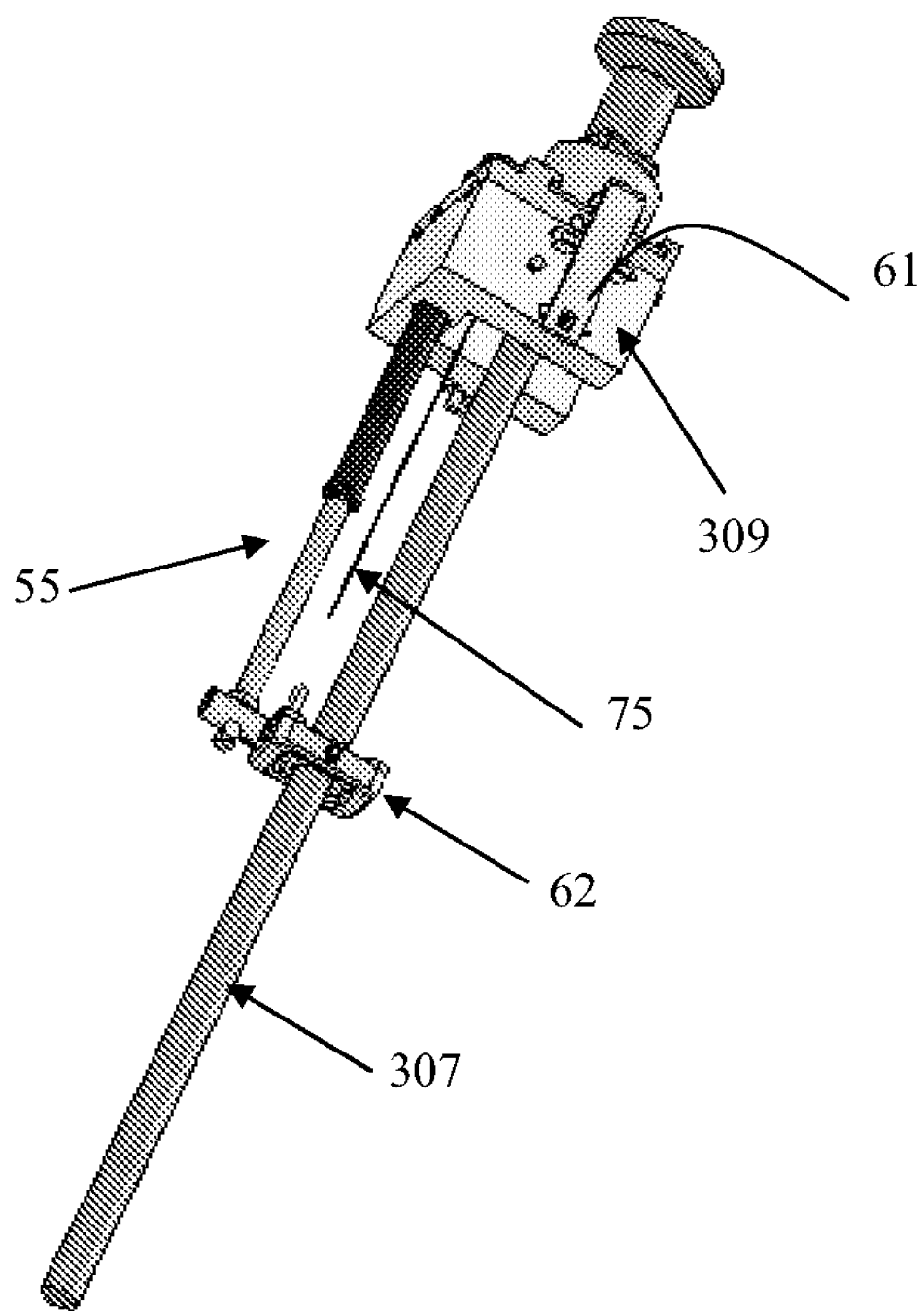


Fig. 6

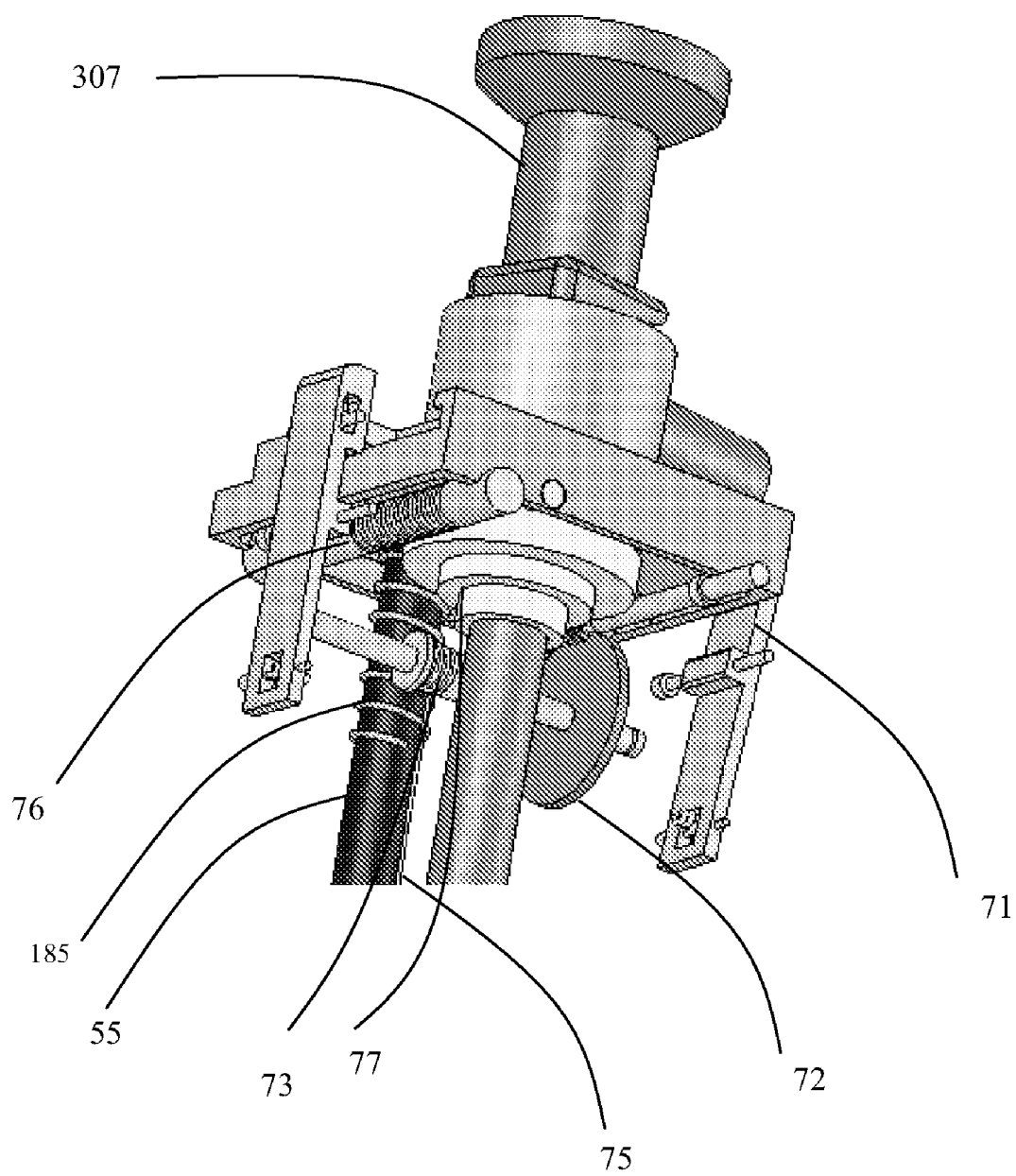


Fig. 7

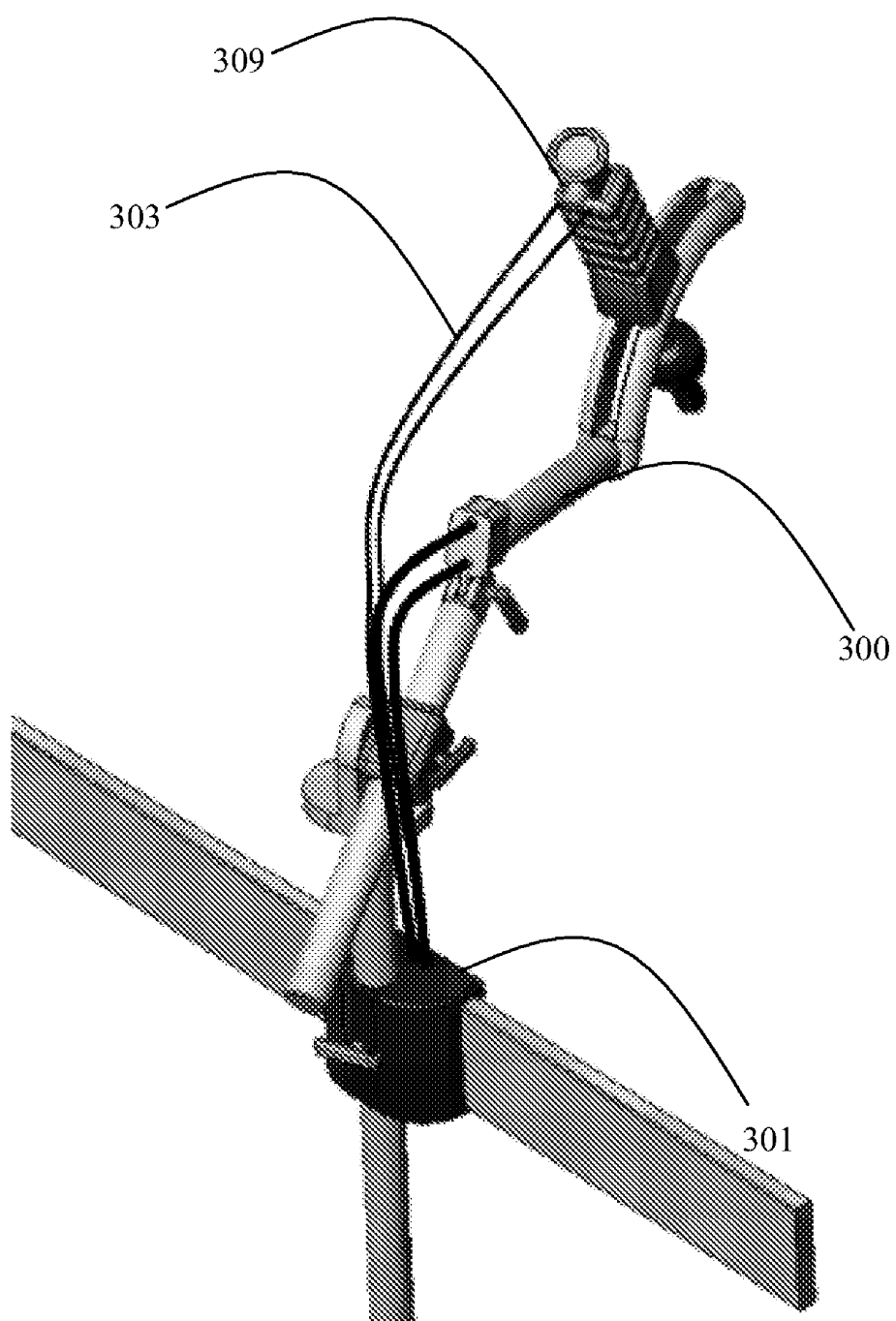


Fig. 8a

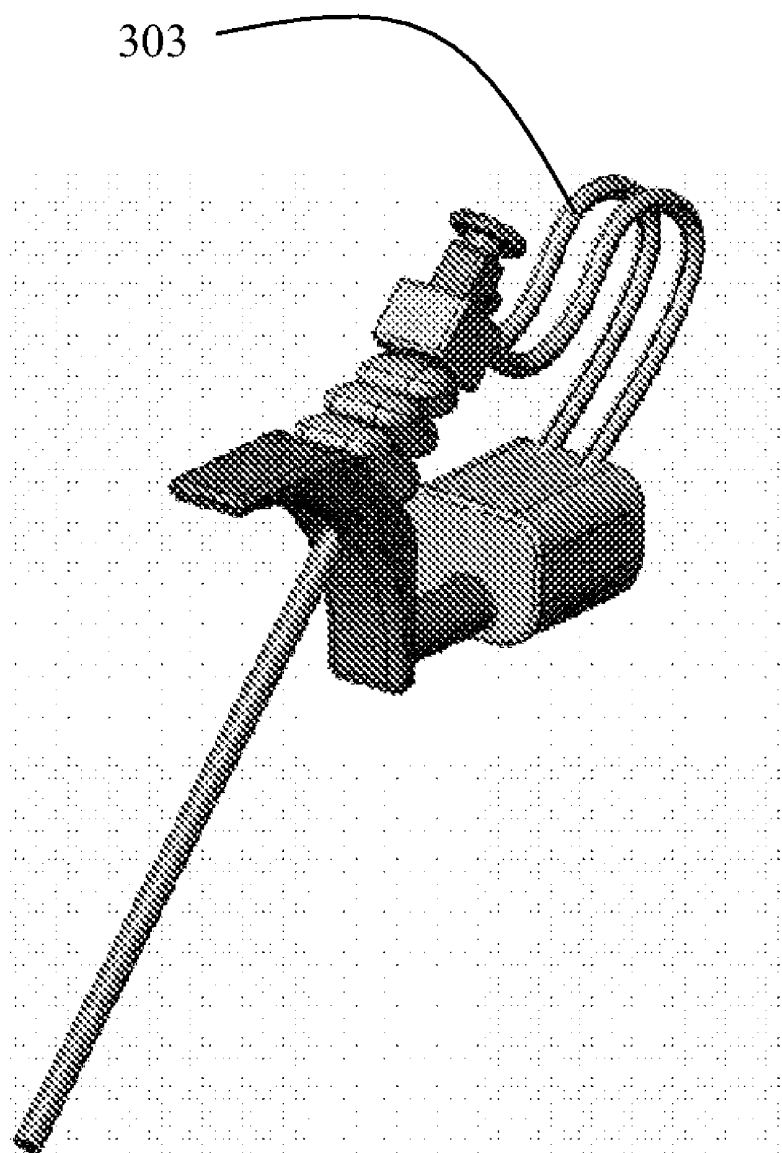


Fig. 8a

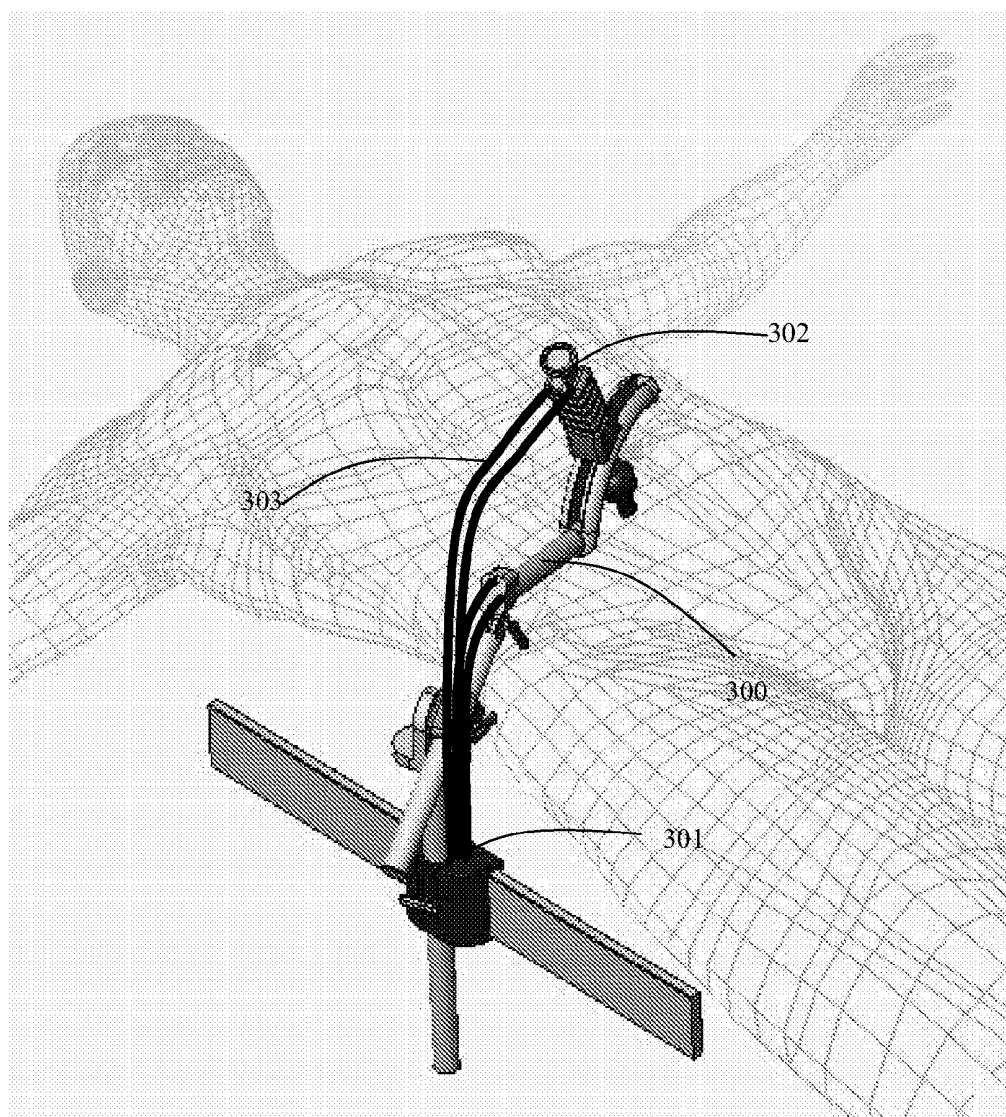


Fig. 8c

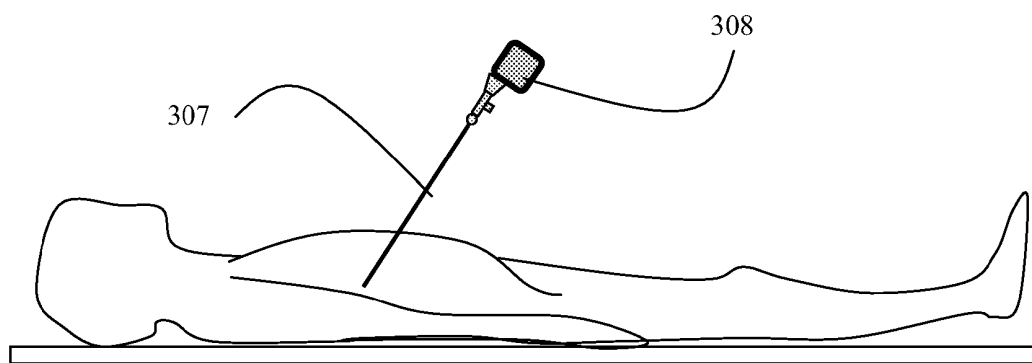


Fig. 9

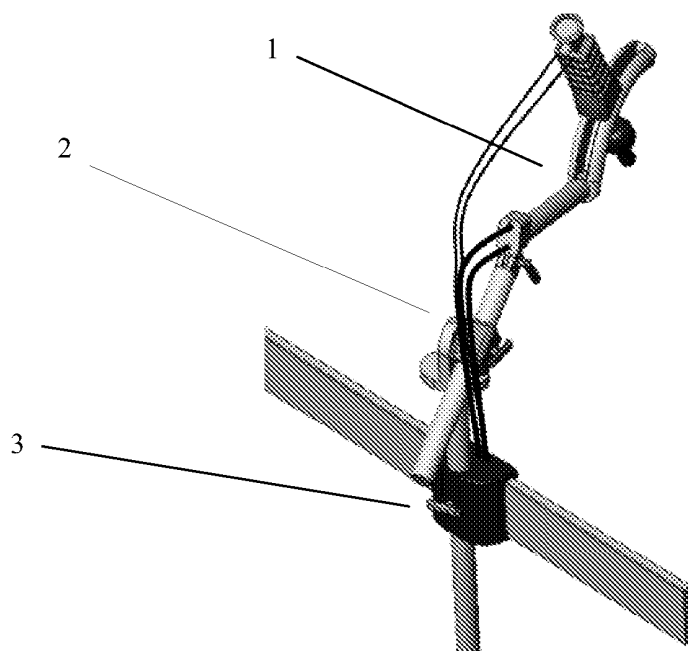


Fig. 10

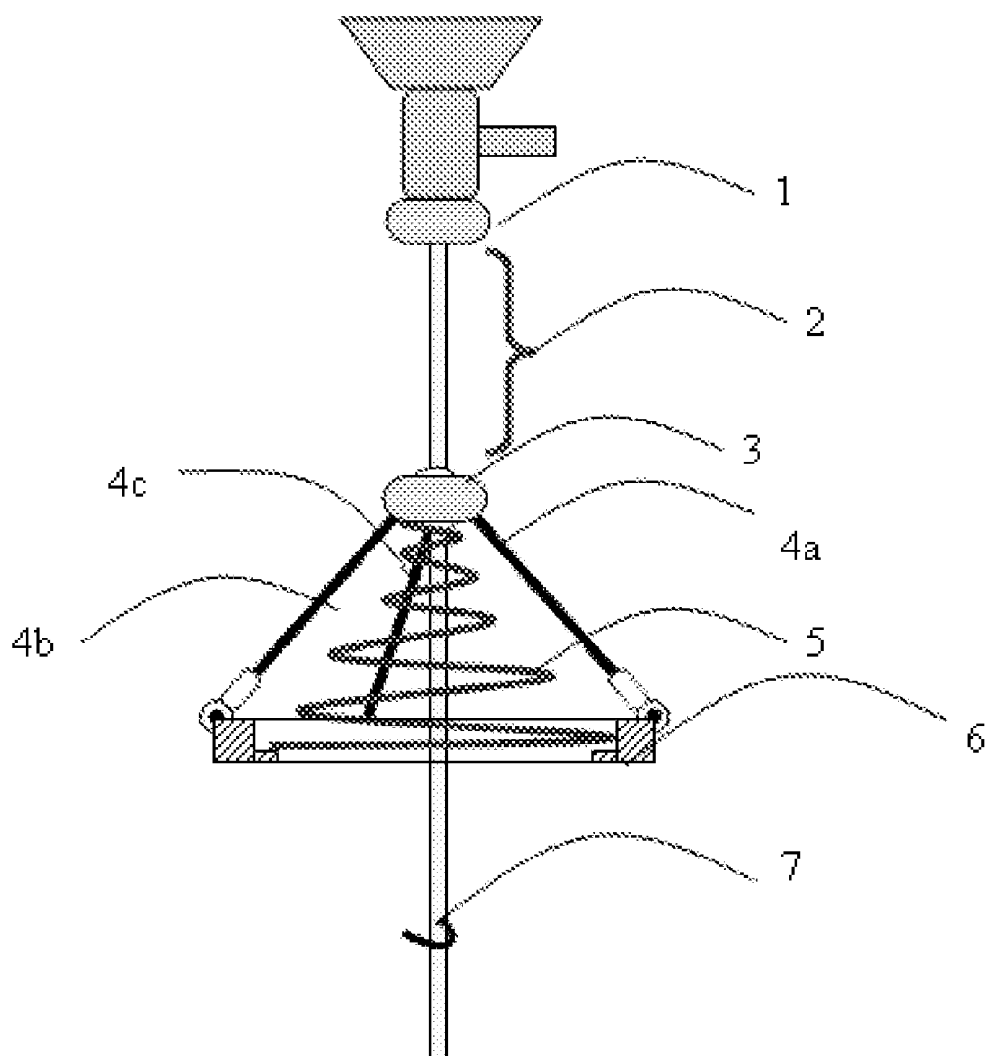


Fig. 11

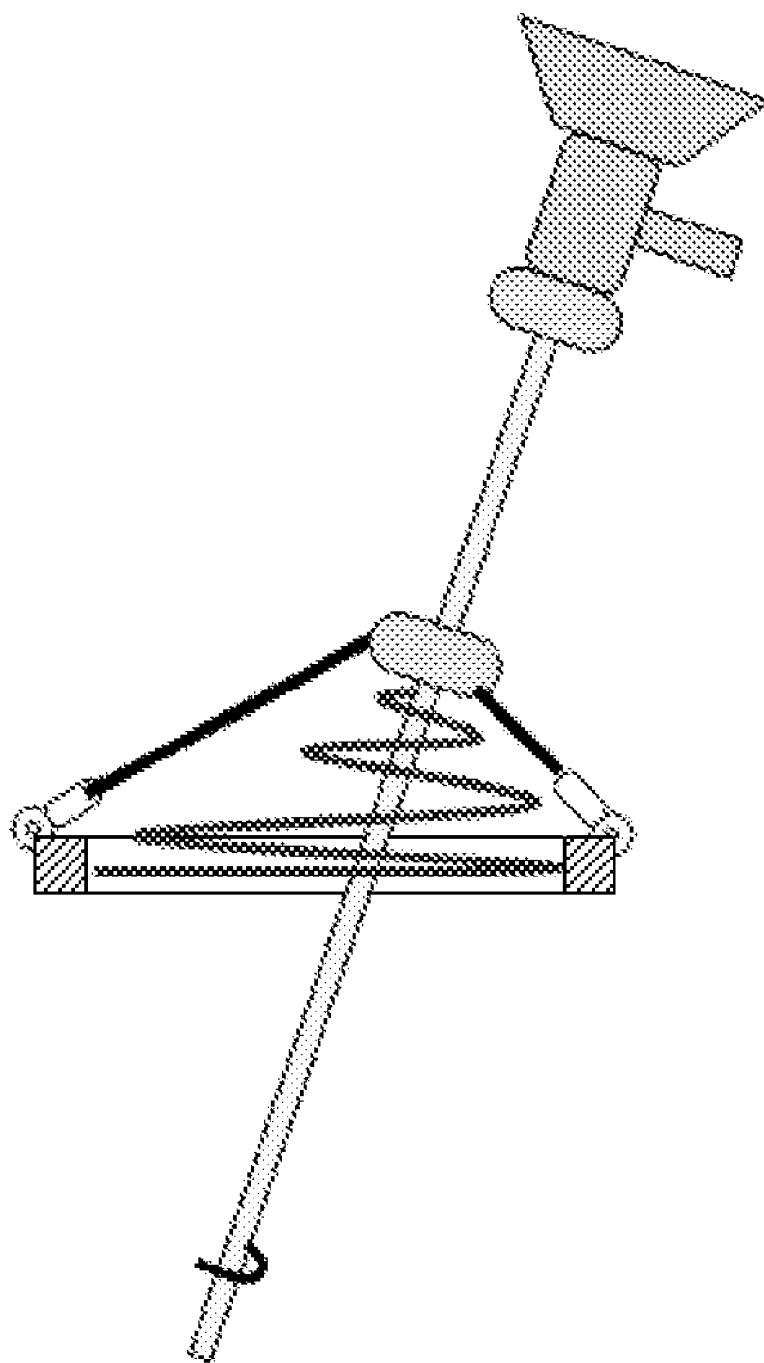


Fig. 12

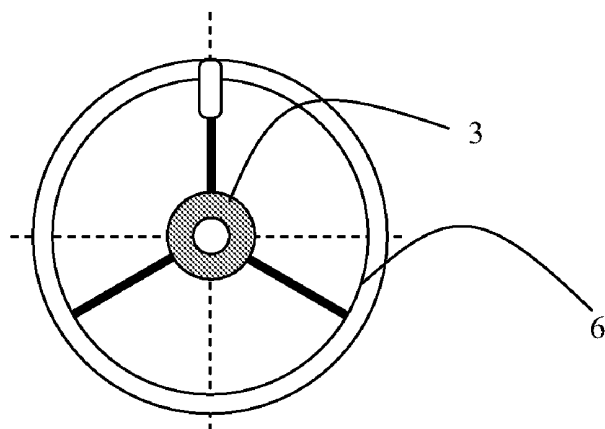


Fig. 13

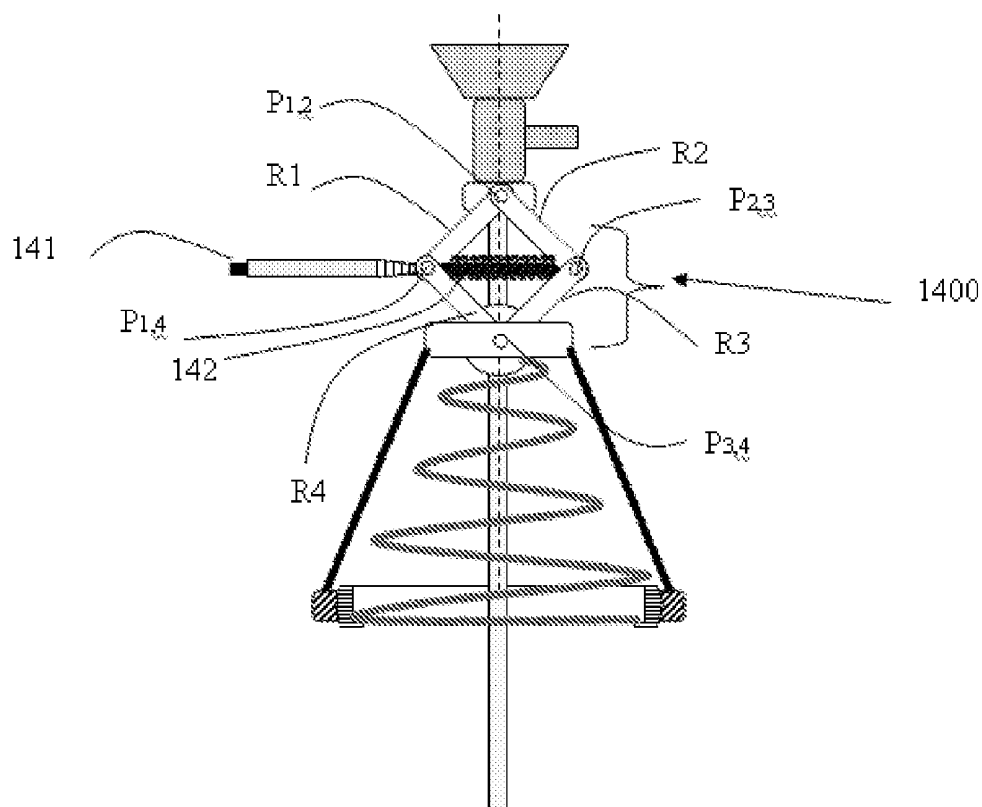


Fig. 14

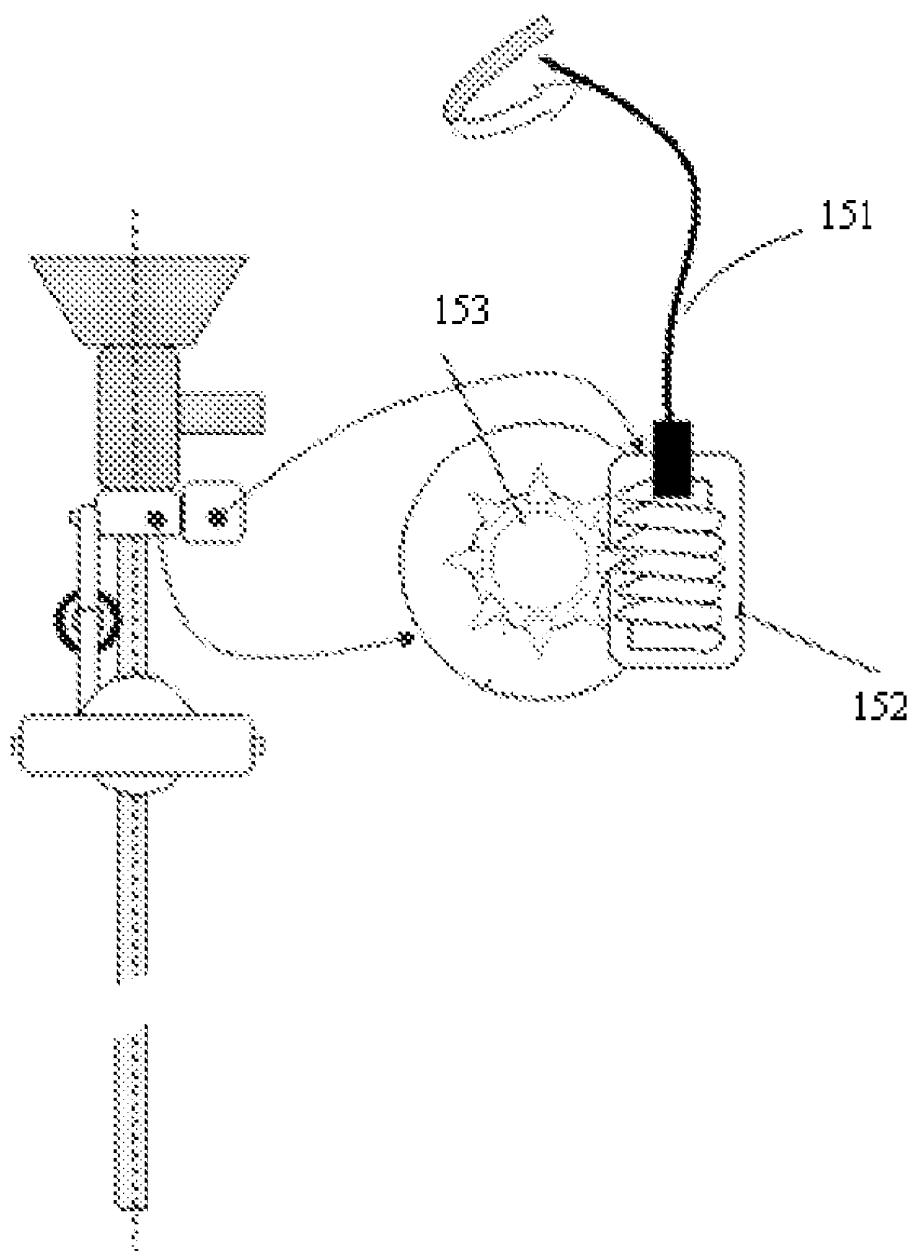


Fig. 15

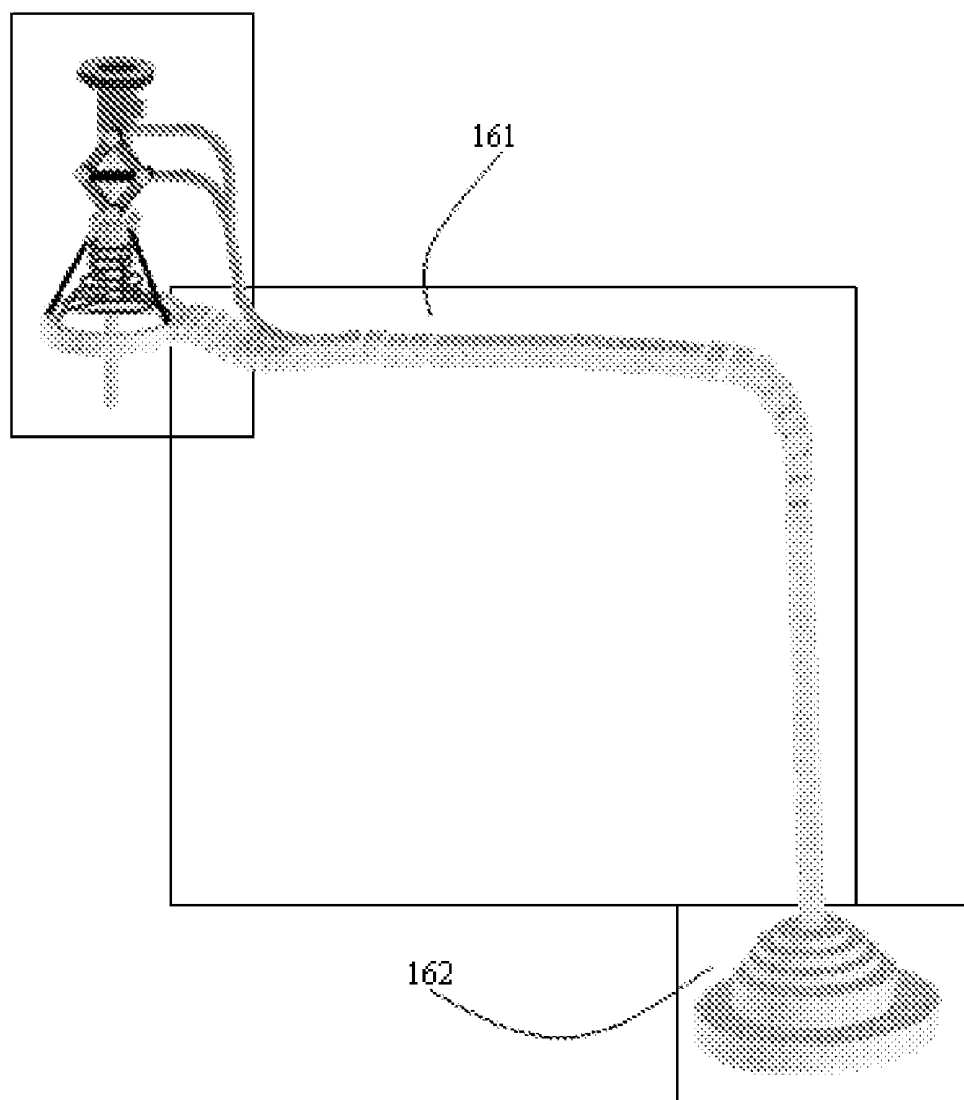


Fig. 16

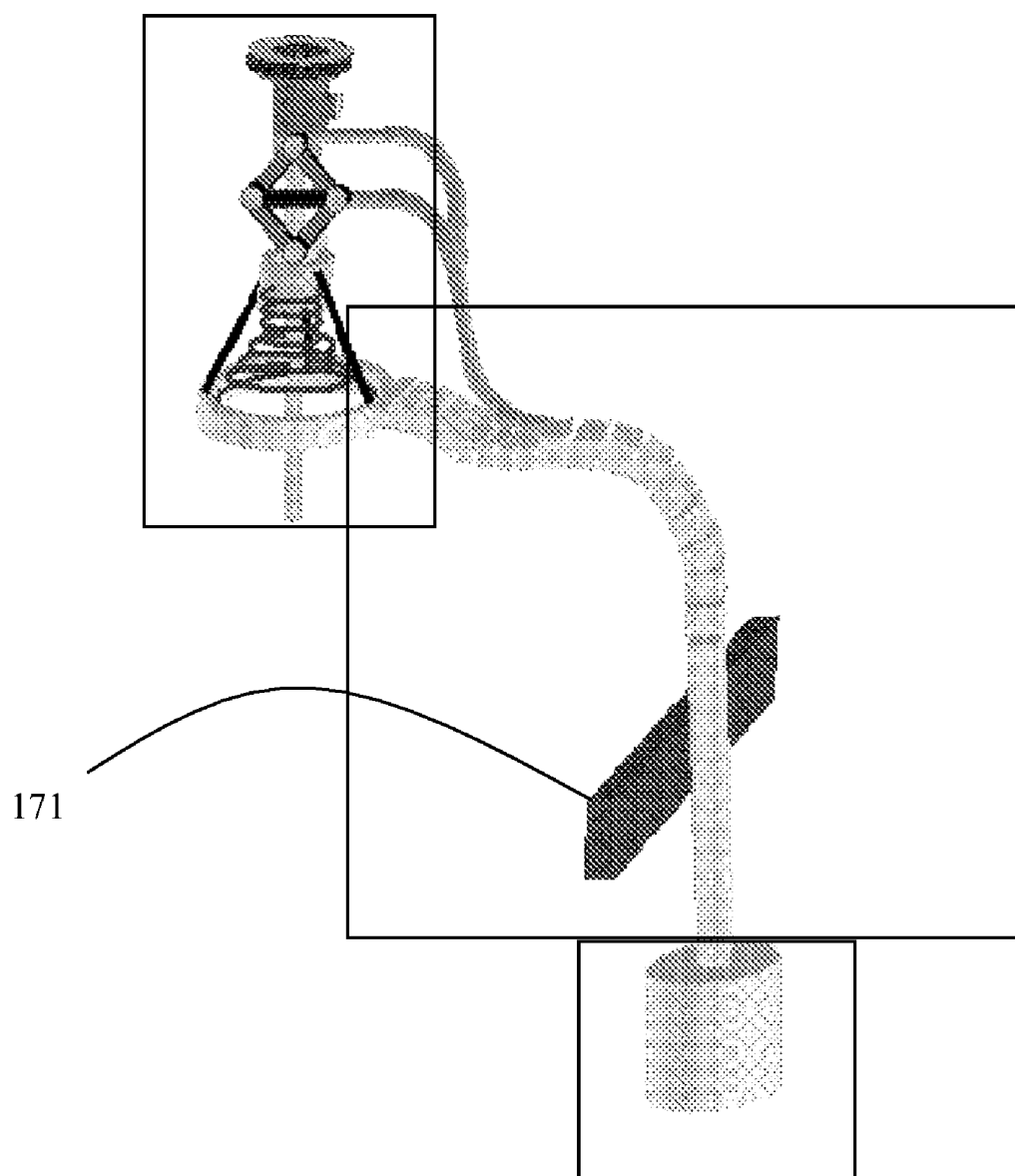


Fig. 17

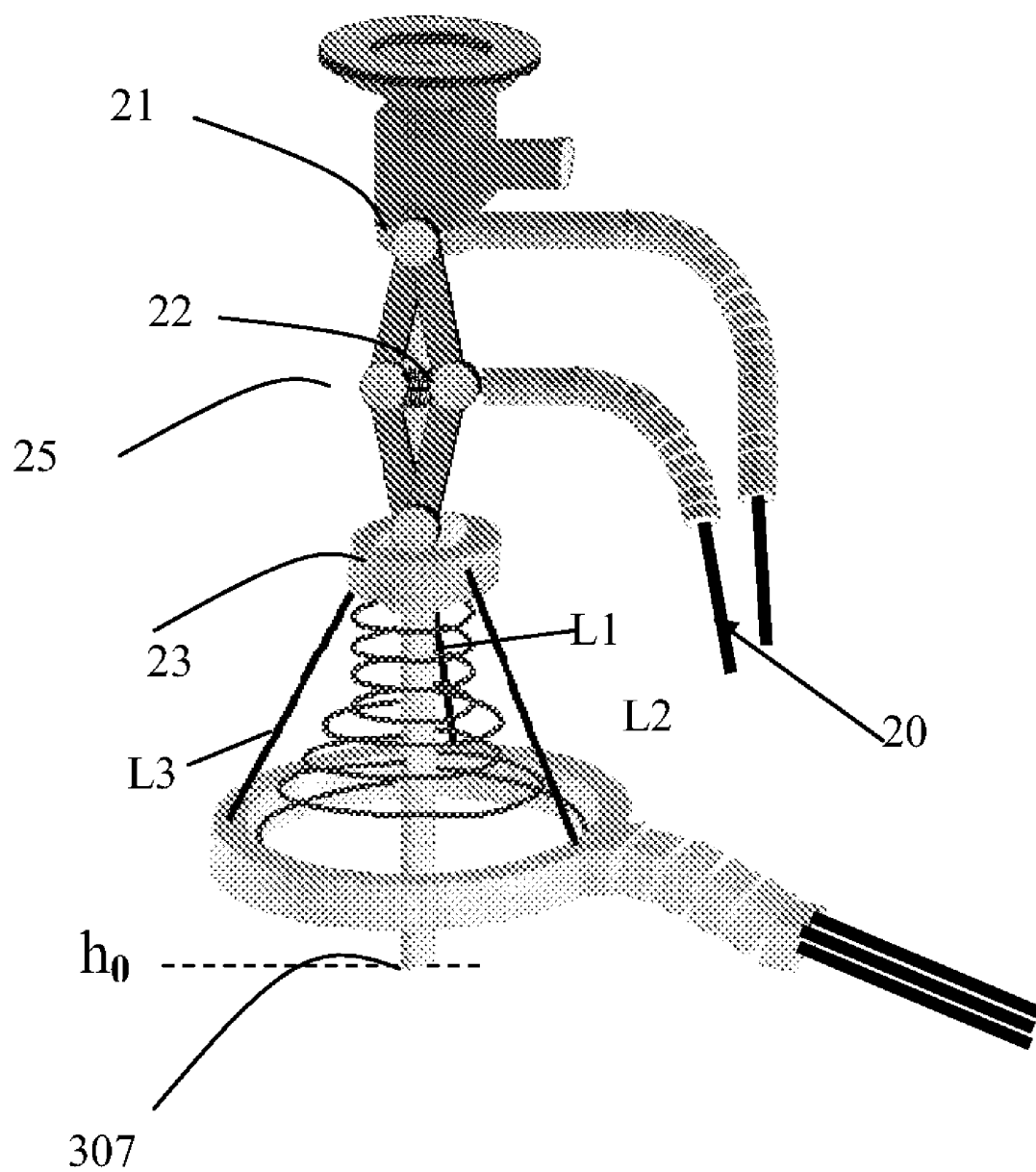


Fig. 18a

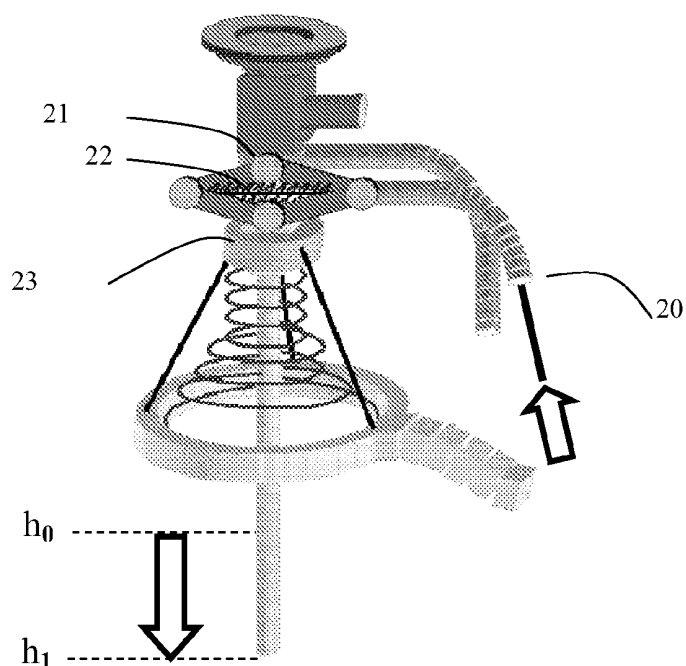


Fig. 18b

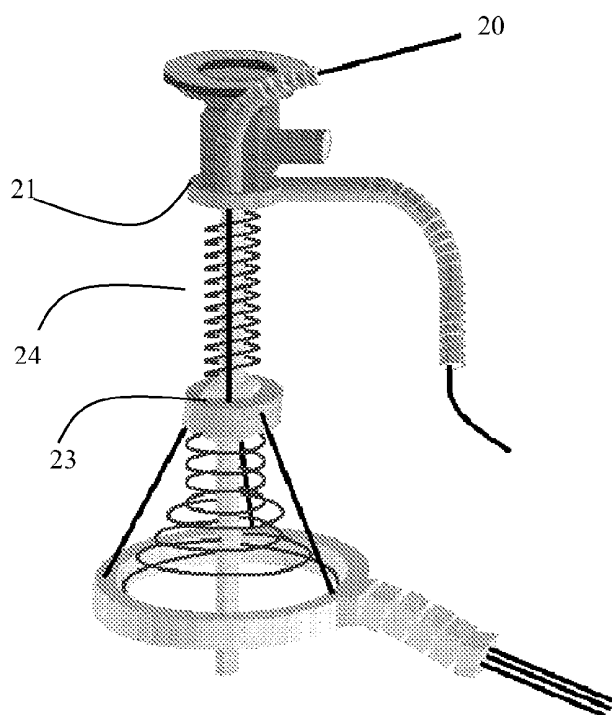


Fig. 19a

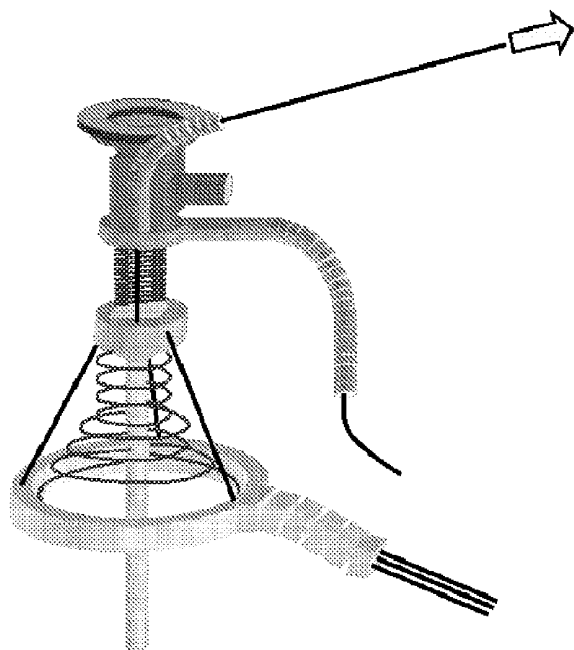


Fig. 196

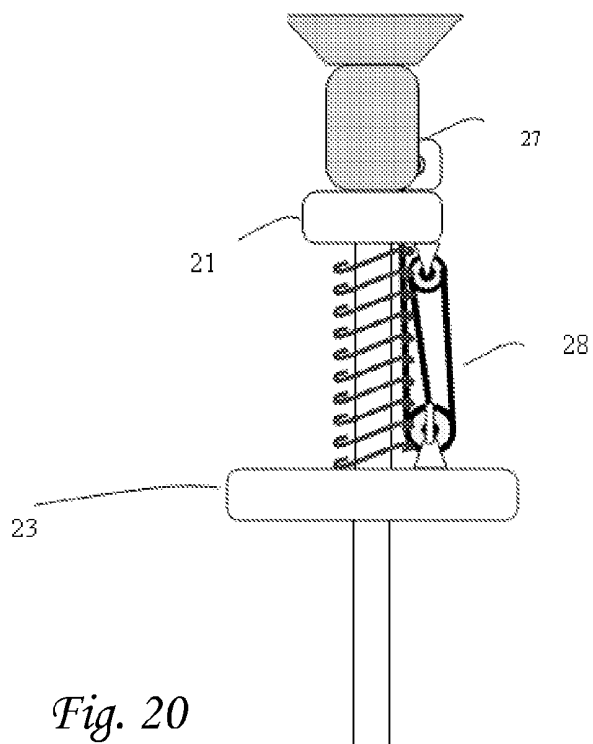


Fig. 20

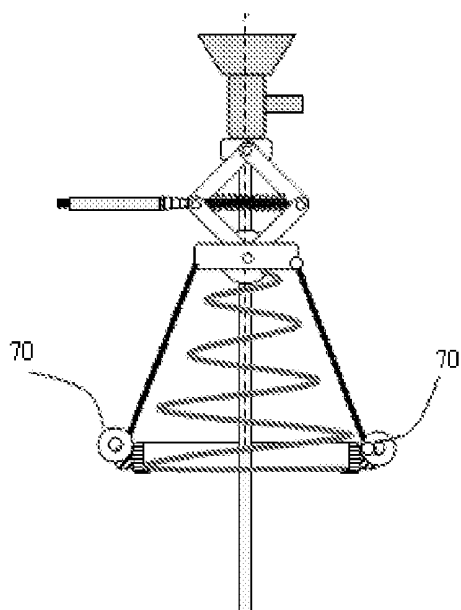


Fig. 21

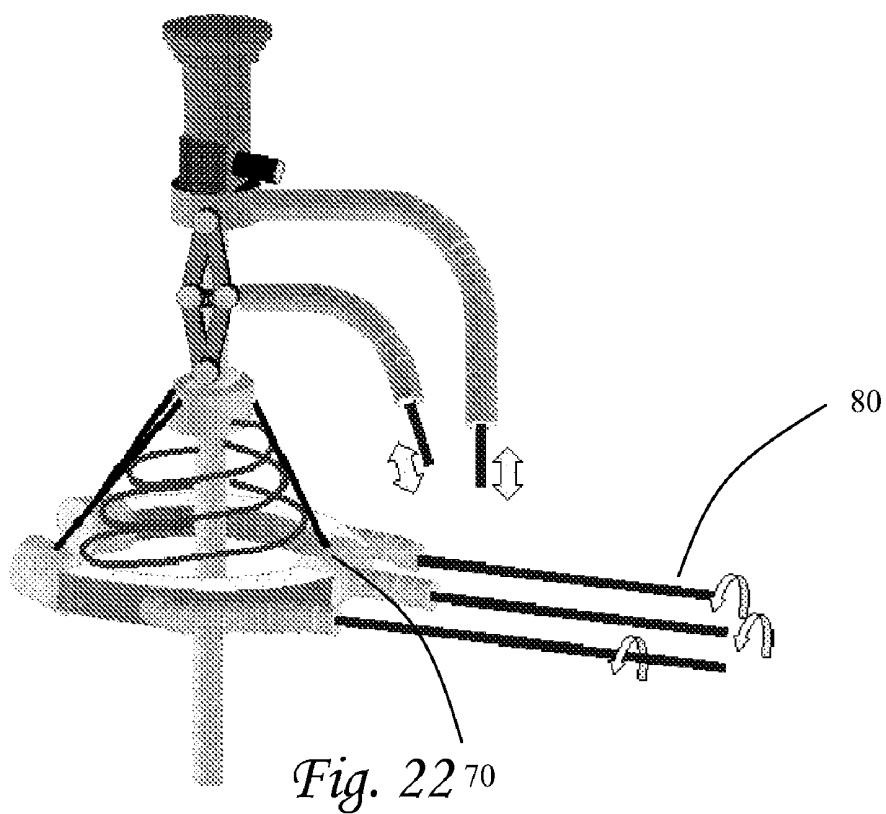


Fig. 22 70

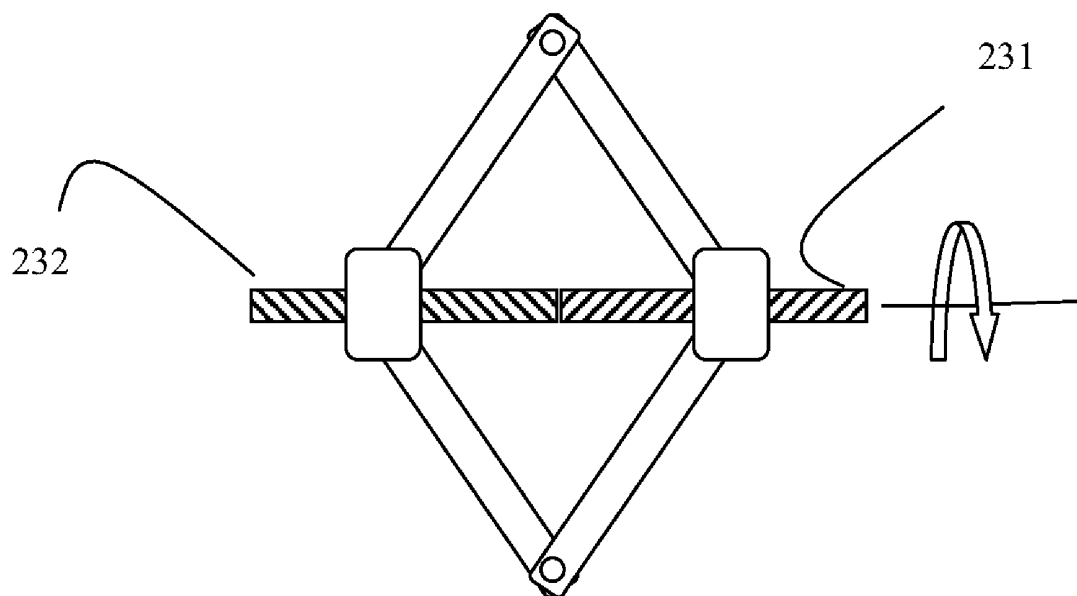


Fig. 23

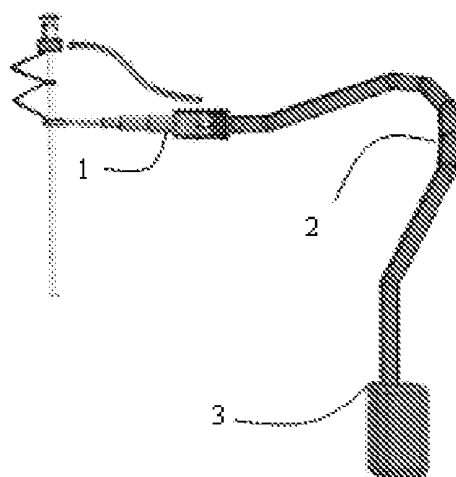


Fig. 24

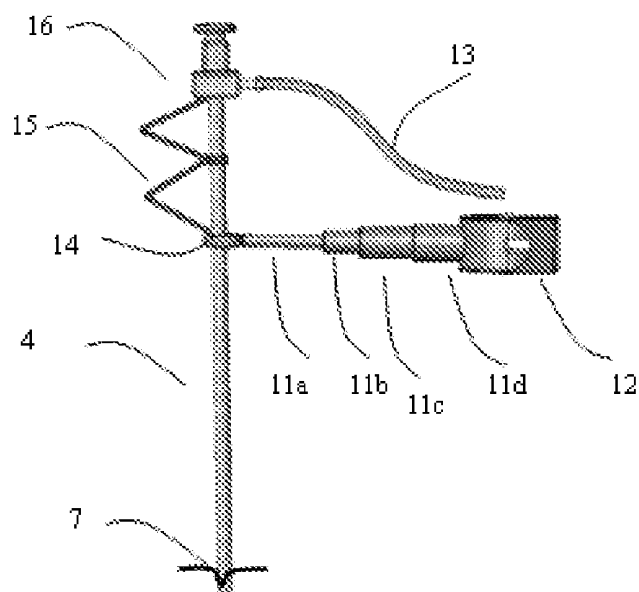


Fig. 25

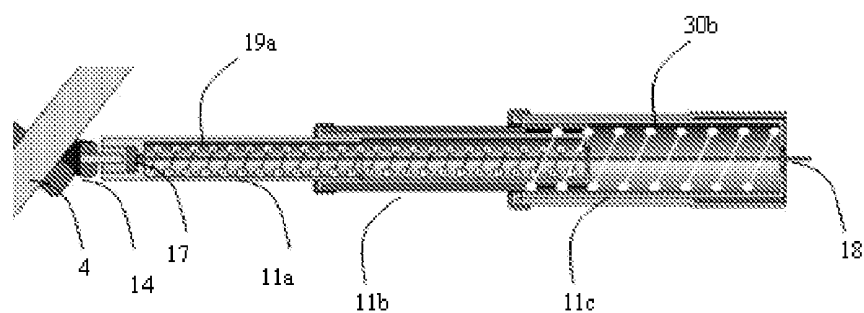


Fig. 26

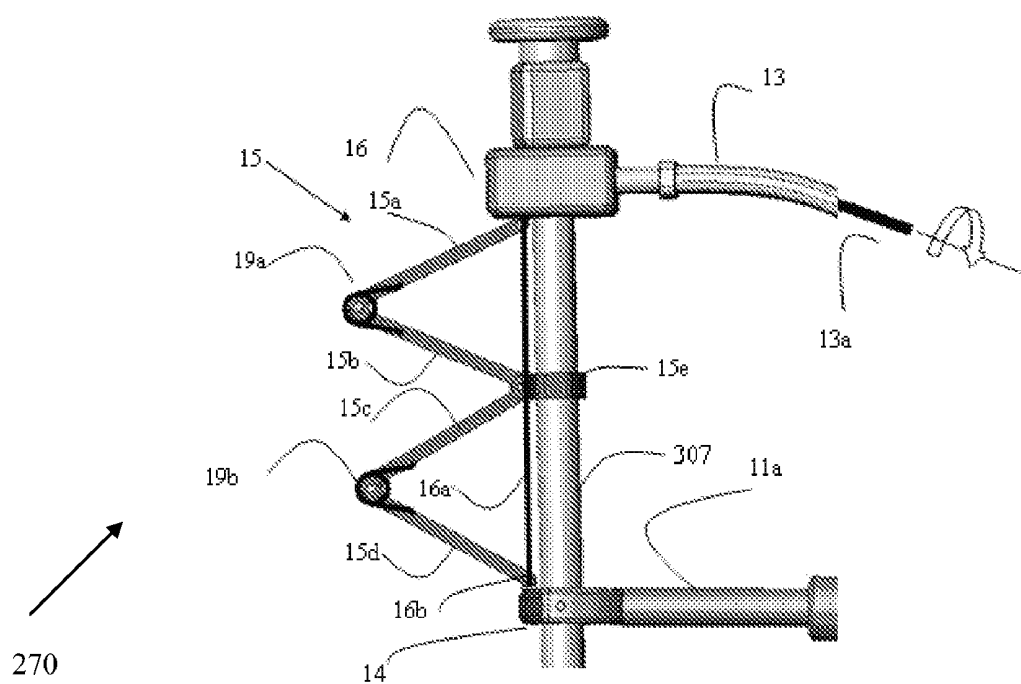


Fig. 27

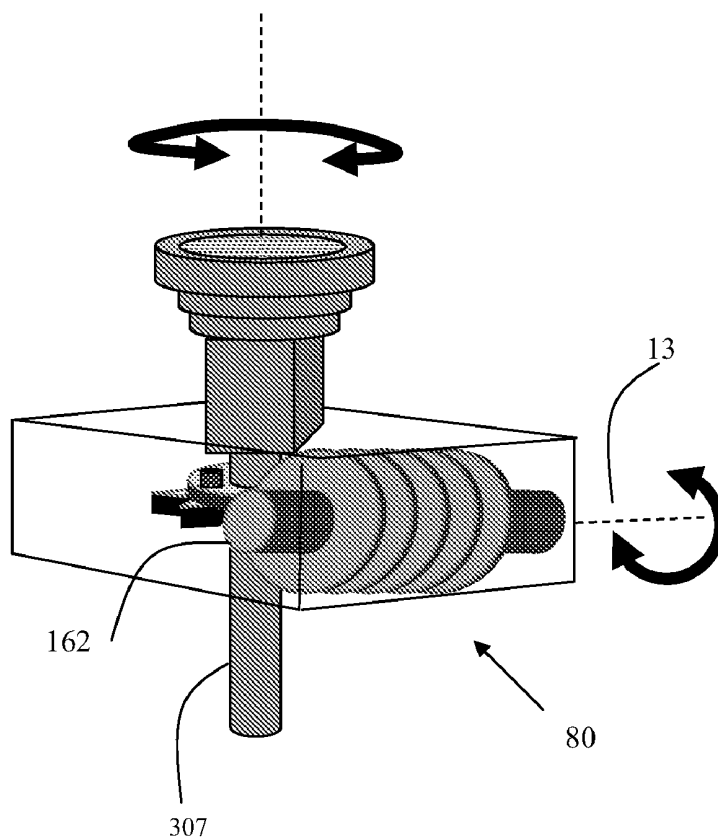


Fig. 28a

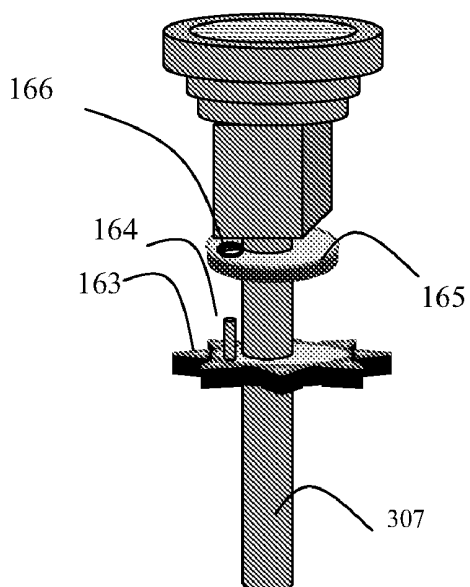


Fig. 28b

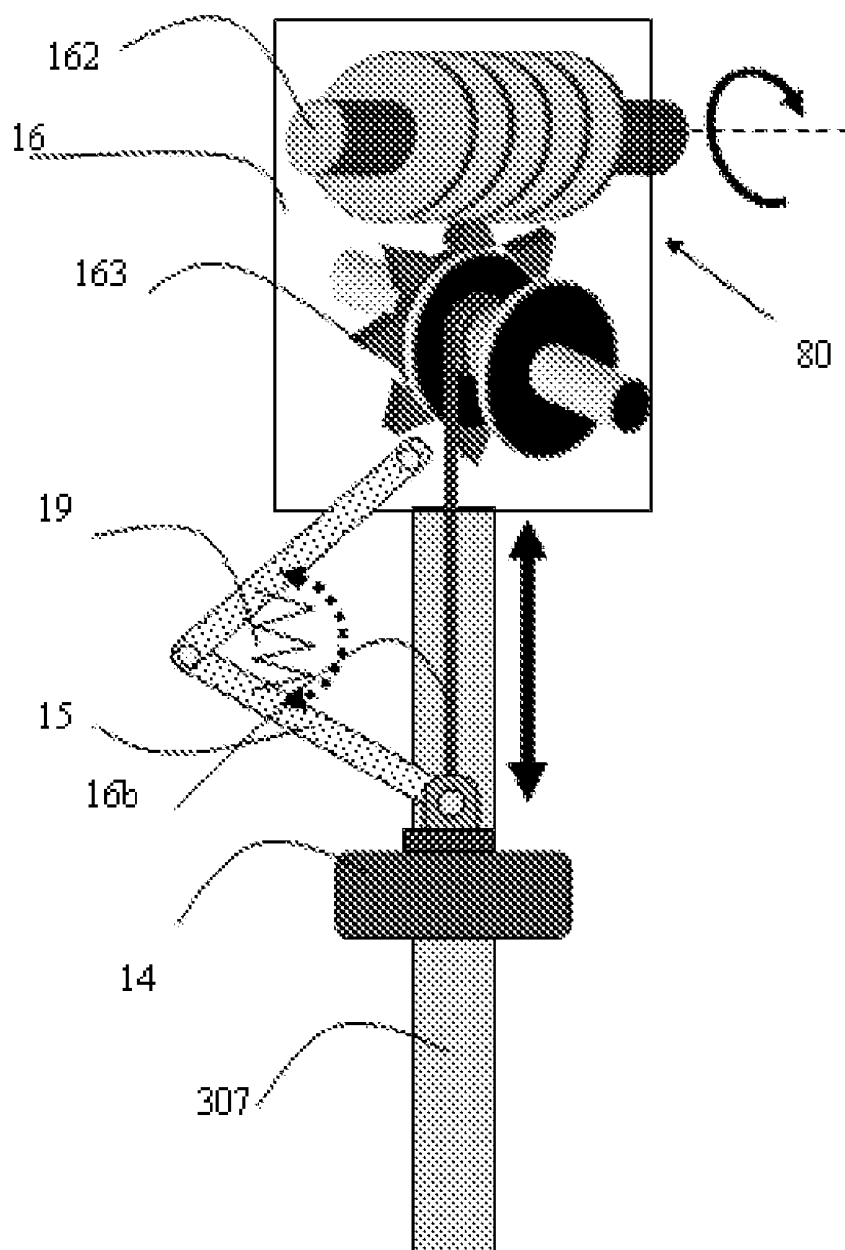


Fig. 28c

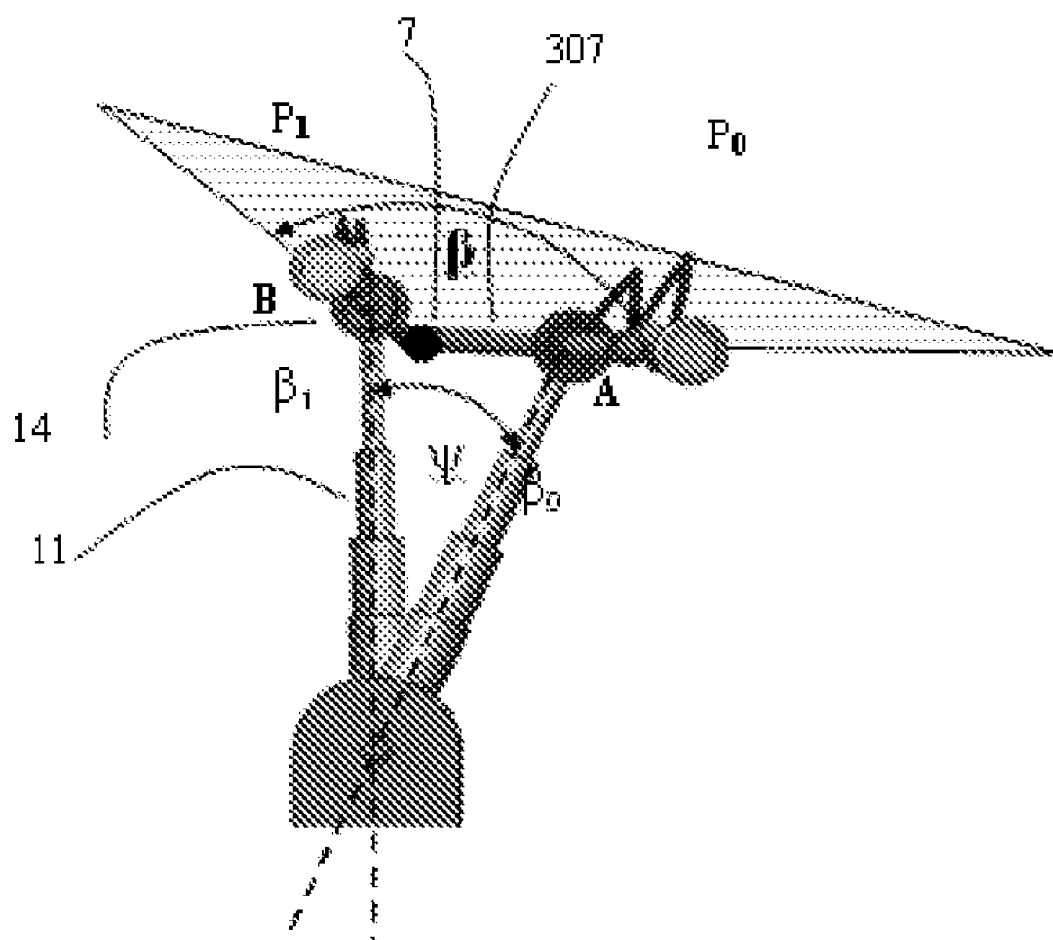


Fig. 31

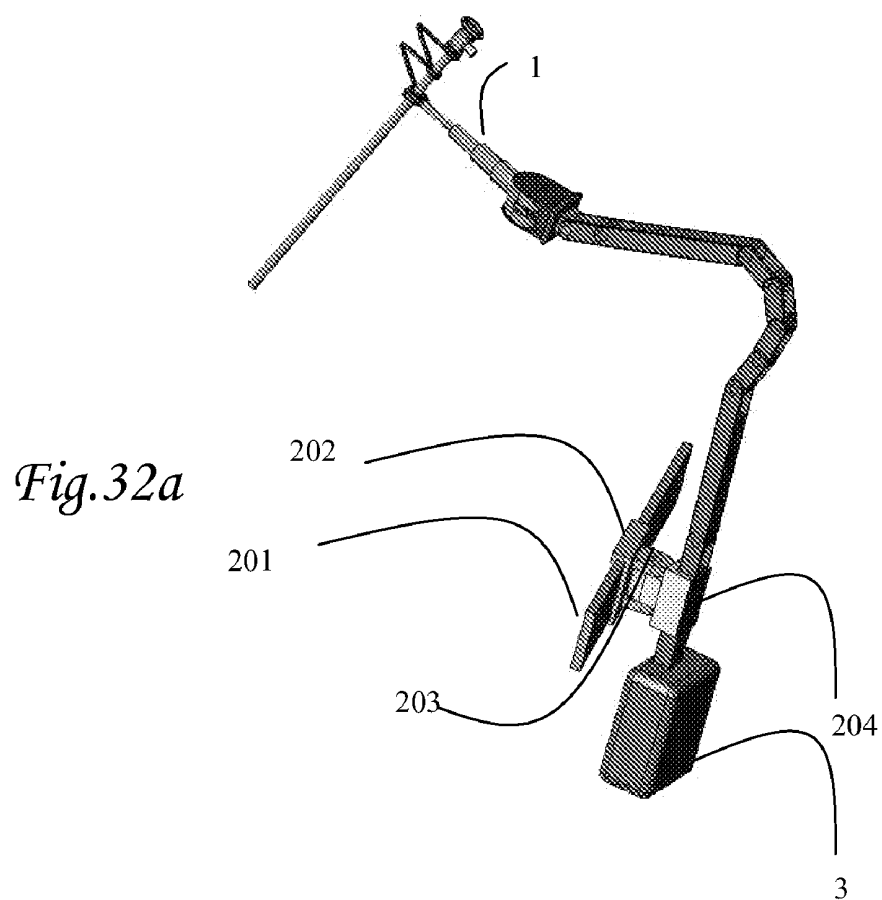
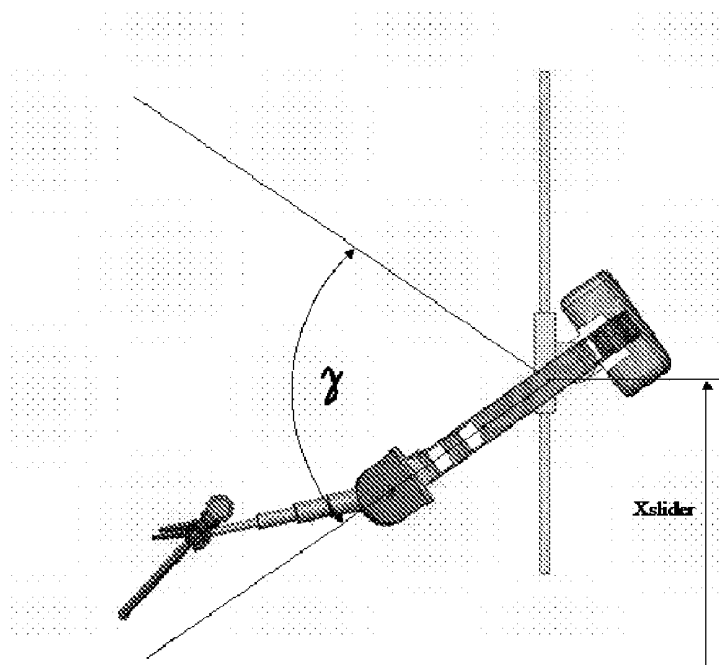


Fig. 32b



CAMERA HOLDER DEVICE AND METHOD THEREOF

FIELD OF THE INVENTION

[0001] The present invention discloses a camera holder device and mechanism for laparoscopic surgery. The camera holder device is easily installed and disassembled, comfortable to use, not limiting the dexterity of the surgeon, having small physical dimension and inexpensive.

BACKGROUND OF THE INVENTION

[0002] In laparoscopic surgery, the surgeon performs the operation through small holes using long instruments and observing the internal anatomy with an endoscope camera. The endoscope is conventionally held by a camera assistant since the surgeon must perform the operation using both hands. The surgeon performance is largely dependent on the camera position relative to the instruments and on a stable image shown at the monitor; also the picture shown must be in the right orientation. The main problem is the difficulty for the assistant to keep the endoscope in the right spatial position, to hold the endoscope steadily, keeping the scene in the right orientation. To overcome these problems, several new technologies have been developed, using robots to hold the endoscope while the surgeon performs the procedure, e.g., Lapman, Endoassist etc. But these technologies are expensive, difficulty installed, uncomfortable to use, limiting the dexterity of the surgeon and having physical dimension much bigger than all operating tools. Relatively to the required action, they also move in big bounds with several arms movement. Another robot, LER (which was developed by the TIMC-GMCAO Laboratory) US. Patent application No. 200/6100501 Consists of a compact camera-holder robot that rests directly on the patient's abdomen and an electronic box containing the electricity supply and robot controllers. LER has relatively small dimensions but has a 110 mm diameter base ring that must be attached, or be very close to patient skin. This ring occupies place over the patient body limiting the surgeon activities: choosing the place of the other trocars, changing the surgeon to usual way of making the procedure, forcing sometimes the setup process to be as long as 40 minutes. Also the LER has only 3 degrees of freedom and have no ability to control the orientation of the picture shown to surgeon (the LER can not rotate the endoscope around its longitudinal axis).

[0003] Reference is made now to FIGS. 1a, 1b, 1c, presenting a schematic illustration of the prior art which describes these technologies.

[0004] Laparoscopic surgery is becoming increasingly popular with patients because the scars are smaller and their period of recovery is shorter. Laparoscopic surgery requires special training of the surgeon or gynecologist and the theatre nursing staff. The equipment is often expensive and not available in all hospitals. During laparoscopic surgery it is often required to shift the spatial placement of the endoscope in order to present the surgeon with the optimal view. Conventional laparoscopic surgery makes use of either human assistants that manually shift the instrumentation or alternatively robotic automated assistants (such as JP patent No. 06063003).

[0005] However, even the improved technologies are still limiting the dexterity of the surgeon and failing to provide

four degrees of freedom. Another disadvantage of those technologies is the lack of ability to control the spatial position of an endoscope tube to any orientation during said laparoscopic surgery, such that the surgeon reaches any desired area within the working envelope in operated body.

[0006] Therefore, there is still a long felt need for a camera holder that would allow holding and controlling the endoscope steadily without limiting the dexterity of the surgeon and that will provide four degrees of freedom. Furthermore, there is still a long felt need for a camera holder that will provide the ability to control the spatial position of an endoscope tube to any orientation during said laparoscopic surgery, such that the surgeon reaches any desired area within the working envelope in operated body.

SUMMARY OF THE INVENTION

[0007] It is one object of the invention to disclose a camera holder, useful for laparoscopic surgery; wherein said camera holder is provided with means of manipulation in four degrees of freedom; further wherein said camera holder is provided with means of controlling the spatial position of an endoscope tube to any orientation during said laparoscopic surgery, such that said endoscope reaches any desired area within the working envelope in an operated body.

[0008] It is another object of the invention to disclose the camera holder as defined above, wherein said camera holder is adapted to have small physical dimension.

[0009] It is another object of the invention to disclose the camera holder as defined above, wherein said camera holder comprises:

[0010] a. a housing (309); said housing is adapted to be connected and disconnected to said endoscope; said housing comprises:

[0011] i. at least one zoom mechanism;

[0012] ii. at least one endoscope rotation mechanisms;

[0013] b. rotating DF (304); and

[0014] c. sliding DF (305).

[0015] It is another object of the invention to disclose the camera holder as defined above, wherein said camera holder additionally comprises:

[0016] a. motor house;

[0017] b. means adapted to transmit movement to said zoom mechanism;

[0018] c. means adapted to transmit movement to said endoscope rotation mechanism;

[0019] d. means adapted to transmit movements to said endoscope rotating OF;

[0020] e. means adapted to transmit movements to the sliding DF.

[0021] It is another object of the invention to disclose the camera holder as defined above, wherein said zoom mechanism is adapted to provide a zoom action; further wherein said endoscope rotation mechanism is adapted to rotate said endoscope about its long axis; further wherein said endoscope rotation mechanism and/or said zoom mechanism

and/or said rotating DF and/or said sliding DF are adapted to be independent of other moving parts of said camera holder mechanism.

[0022] It is another object of the invention to disclose the camera holder as defined above, wherein said camera holder is disasposable.

[0023] It is another object of the invention to disclose the camera holder as defined above, wherein said camera holder additionally comprises a quick release handle adapted to disassemble said endoscope out of said housing without changing any of said degrees of freedom.

[0024] It is another object of the invention to disclose the camera holder as defined above, wherein said camera holder additionally comprising a telescopic guide; said telescopic guide is adapted to provide said endoscope movement along said endoscope longitudinal axis.

[0025] It is another object of the invention to disclose the camera holder as defined above, additionally comprising:

[0026] a. a zoom ring (1);

[0027] b. orientation ring (3);

[0028] c. at least two cables **4a** and **4b**; said cables **4a** and **4b** are characterized by having length of L_1 and L_2 ;

[0029] d. a spring (5); said spring is characterized by having a resistance K; and

[0030] e. a basis ring (6);

[0031] wherein lengths of L_1 , L_2 are changeable in conjunction with said spring's resistance K, thereby said orientation ring is moved relatively to said basis ring.

[0032] It is another object of the invention to disclose the camera holder as defined above, wherein said rotation mechanism comprises at least one cable; at least one worm gear; said cable is adapted to rotate said worm gear such that said endoscope is rotated.

[0033] It is another object of the invention to disclose the camera holder as defined above, wherein said rotation mechanism comprises at least one pulley block; said pulley block are adapted to control the spatial angular position of said endoscope.

[0034] It is another object of the invention to disclose the camera holder as defined above, wherein said camera holder additionally comprising means such that said camera holder is adapted to be portable.

[0035] It is another object of the invention to disclose the camera holder as defined above, wherein said means comprising (a) at least one adjustable arm; and (b) a basis comprising at least one motor; said adjustable arm couples said camera holder and said basis.

[0036] It is another object of the invention to disclose the camera holder as defined above, wherein said zoom mechanism is selected from a group comprising adjustment cable mechanism, parallelogram rods mechanism, a spring mechanism, a reduction force mechanism, rotating cable mechanism and a two springs zoom mechanism.

[0037] It is another object of the invention to disclose the camera holder as defined above, wherein said camera holder

comprising a manipulating endoscope mechanism (1); a force carriage system (2); and a force source (3).

[0038] It is another object of the invention to disclose the camera holder as defined above, wherein said manipulating endoscope mechanism comprises:

[0039] a. at least one cable;

[0040] b. at least one spring; and

[0041] c. at least one rod;

[0042] said force carriage system comprises:

[0043] a. at least one cable;

[0044] b. at least one chain; and

[0045] c. at least one rod;

[0046] said force source comprises

[0047] a. at least one motor; and/or at least one actuator; at least one piston.

[0048] It is another object of the invention to disclose a method for controlling the spatial position of endoscope tube to any orientation in laparoscopic surgery, such that the surgeon reaches any desired area within the working envelope in operated body. The method comprises step selected inter alia from (a) obtaining a camera holder as defined above; (b) assembling said endoscope to said housing; and (c) controlling and manipulating said endoscope such that an optimal field view is obtained; wherein said step of controlling and manipulating said endoscope is providing said endoscope movement in four degrees of freedom.

[0049] It is another object of the invention to disclose the method as defined above, additionally comprising the step of zooming in and/or zooming out of said desired area such that more precisions is obtained.

[0050] It is another object of the invention to disclose the method as defined above, wherein said step of zooming in and/or zooming out additionally comprises the step of moving said endoscope along said endoscope longitudinal axis.

[0051] It is another object of the invention to disclose the method as defined above, additionally comprising the step of rotating said endoscope.

[0052] It is another object of the invention to disclose the method as defined above, additionally comprising the step of disassembling said endoscope to said housing.

[0053] It is another object of the invention to disclose the method as defined above, additionally comprising the step of controlling the rotation angle of said endoscope along said endoscope long axis.

[0054] It is another object of the invention to disclose the method as defined above, additionally comprising the step of selecting said zoom mechanism from a group comprising adjustment cable mechanism, parallelogram rods mechanism, a spring mechanism a reduction force mechanism, rotating cable mechanism and a two springs zoom mechanism.

[0055] It is still an object of the invention to disclose the method as defined above, additionally comprising the step of adjusting said camera holder to be portable.

[0056] It is lastly an object of the invention to disclose the method as defined above, additionally comprising the step of disassembling the endoscope out of the zoom mechanism without changing any degree of freedom of the spatial position of said endoscope, by activating said endoscope independently of other moving parts of the mechanism, such that the entire system does not have to be re-positioned.

BRIEF DESCRIPTION OF THE FIGURES

[0057] In order to understand the invention and to see how it may be implemented in practice, and by way of non-limiting example only, with reference to the accompanying drawing, in which

[0058] FIG. 1*a*, 1*b*, 1*c* present a schematic illustration of prior art technologies;

[0059] FIG. 2 is a schematic view of the camera holder;

[0060] FIG. 3 is a schematic cut view of the camera holder;

[0061] FIG. 4 schematically illustrates a mechanism with only one curved guide;

[0062] FIG. 5 schematically illustrates the four degrees of freedom of the mechanism;

[0063] FIGS. 6 and 7 are schematic view of the telescopic guide;

[0064] FIG. 8*a*, 8*b*, 8*c* schematically present an illustrating example of a camera holder mechanism for laparoscopic surgery;

[0065] FIG. 9 illustrates the way in which the endoscope is inserted through a small incision in the abdomen or chest;

[0066] FIG. 10 presents a schematic and illustrated drawing of the entire system according to one embodiment of the present invention which comprises three main parts a manipulating endoscope mechanism (1); a force carriage system (2); and a manipulating system actuator (3);

[0067] FIG. 11 presents a schematic illustration of the camera holder according to another embodiment of the present invention;

[0068] FIG. 12 is a schematic view of the camera holder illustrating the motion of the orientation ring relatively to the basis ring;

[0069] FIG. 13 is a schematic view of the orientation ring different position;

[0070] FIG. 14 is a schematic view of the “adjustment cable” zoom mechanism according to one embodiment of the present invention;

[0071] FIG. 15 presents a schematic description of the rotation mechanism;

[0072] FIG. 16 represents the portable feature of the mechanism;

[0073] FIG. 17 is a schematic view of the mechanism placed beside a bed;

[0074] FIG. 18*a*, 18*b*, 19*a*, 19*b*, 20 represent three different options for the zoom mechanism: 18*a* and 18*b* with

“parallelogram rods mechanism”; 19*a* and 19*b* with a “spring mechanism”; and 20 with a “reduction force device”;

[0075] FIG. 21 presenting a schematic section view of the pulley blocks located on the endoscope motion mechanism;

[0076] FIG. 22 is a three-dimension schematic view of FIG. 21;

[0077] FIG. 23 is a schematic view of the “rotating cable” zoom mechanism obtained by rotating cable which turns a central screw with joins in different directions;

[0078] FIG. 24 presents a schematic and illustrated drawing of the entire system according to one embodiment of the present invention which comprises three main parts a manipulating endoscope mechanism (1); a force carriage system (2); and a manipulating system actuator (3);

[0079] FIG. 25 presents a schematic illustration of the manipulating endoscope mechanism (1);

[0080] FIG. 26 presents a schematic cut view along the sliding links 11*a*, 11*b*, 11*c* of FIG. 25;

[0081] FIG. 27 presents the zoom mechanism, according to another embodiment of the present invention (the “two springs zoom mechanism”);

[0082] FIG. 28*a*, 28*b* and 28*c* schematically present the rotation mechanism according to another embodiment of the present invention;

[0083] FIG. 29 schematically presents the envelope of the endoscope range of movement;

[0084] FIG. 30 schematically presents the way the mechanism acts to controls one angle of the endoscope by changing the total length of the telescopic arm;

[0085] FIG. 31 schematically presents the way the mechanism acts to controls another angle (β) of the endoscope by rotating telescopic arm;

[0086] FIG. 32*a* schematically presents the portable feature of the mechanism; and,

[0087] FIG. 32*b* schematically presents an upper view of the position abilities of the system: the rotation angle γ , and the horizontal position X slider.

DETAILED DESCRIPTION OF THE EMBODIMENTS

[0088] The following description is provided, alongside all chapters of the present invention, so as to enable any person skilled in the art to make use of the invention and sets forth the best modes contemplated by the inventor of carrying out this invention. Various modifications, however, will remain apparent to those skilled in the art, since the generic principles of the present invention have been defined specifically to provide a camera holder mechanism for laparoscopic surgery.

[0089] The present invention provides a camera holder, useful for laparoscopic surgery. The camera holder is provided with means of manipulation in four degrees of freedom.

[0090] The camera holder is provided with means of controlling the spatial position of an endoscope tube to any

orientation during the laparoscopic surgery, such that the endoscope reaches any desired area within the working envelope in an operated body.

[0091] The present invention also provides a method for controlling the spatial position of endoscope tube to any orientation in laparoscopic surgery, such that the surgeon reaches any desired area within the working envelope in operated body. The method comprises step selected inter alia from (a) obtaining a camera holder mechanism as defined above; (b) assembling the endoscope to the housing; and (c) controlling and manipulating the endoscope such that an optimal field view is obtained; The step of manipulating the endoscope is provided in four degrees of freedom.

[0092] The term “pulley” refers herein after to a wheel with a groove between two flanges around its circumference, the groove normally locates a rope, cable or belt. Pulleys are used to change the direction of an applied force, transmit rotational motion, or realize a mechanical advantage in either a linear or rotational system of motion.

[0093] The term “gimbal” refers herein after to a pivoted support that allows the rotation of an object about a single axis.

[0094] The term “small physical dimension” refers hereinafter to the physical dimensions of a human palm.

[0095] The term “four degrees of freedom” refers herein after to the four independent degrees of freedom illustrated in FIG. 5.

[0096] The term “adjustment cable mechanism” refers herein after to the zoom mechanism described in FIG. 14;

[0097] The term “parallelogram rods mechanism” refers herein after to the zoom mechanism described in FIGS. 18a and 18b;

[0098] The term “spring mechanism” refers herein after to the zoom mechanism described in FIGS. 19a and 19b;

[0099] The term “a reduction force mechanism” refers herein after to the zoom mechanism described in FIG. 20;

[0100] The term “rotating cable mechanism” refers herein after to the zoom mechanism described in FIG. 23;

[0101] The term “two springs zoom mechanism” refers herein after to the zoom mechanism described in FIG. 27;

[0102] The term “zoom leading bars” refers herein after to the bars described in FIG. 25.

[0103] Reference is made now to FIGS. 2 and 3 which illustrate the camera holder device 100.

[0104] As can be seen from FIG. 2, the camera holder 100 comprises a mechanism allowing degrees of freedom (DF) in the rotational direction (denotes herein after as rotating DF) 304, a mechanism allowing degrees of freedom (DF) in sliding (denotes herein after as sliding DF) 305 and housing 309. The housing 309 comprises a rotation and a zoom mechanism. The rotating DF 304, sliding DF 305 and housing 309 can be disposable. Camera 308, endoscope 307 and Trocar 306 can also be seen in FIG. 2. FIG. 2 illustrates the mechanism of the camera holder 100. The camera holder consists two main components: the first part has an arc shape in which the endoscope can be driven back and forth and at the same time can be move from side to side (the sliding DF

and the rotating DF); the second part 309 is characterized by zoom and endoscope rotation properties. The mechanism allows the moving and the positioning of the endoscope in the angles of 0°-90° back and forth and 0°-180° side to side.

[0105] As mention above, the camera holder consists of arc shape housing which moves a gimbal mechanism along an arc shape guide. The base of the arc includes a housing containing a lead screw (15) that moves a nut (10) back and forth. The moving nut is connected to the gimbal with links (20) that transfer the linear nut movement to the gimbals mechanism resulting its movement back and forth along the arc shape guide (the sliding DF). The lead screw housing (back forth screw housing 30) is connected to another mechanism (the rotating DF) which rotates the first part from side to side around the longitudinal axis of the lead screw. This mechanism may also supply at the same time the movements needed to rotate the lead screw. This design allows the motors that move the first part to be connected from a distance preferably by flexible or articulated shafts. The separation is a very useful feature due to the fact that the presence of the mechanism becomes minor.

[0106] The zoom and rotation mechanisms:

[0107] The zoom mechanism and the endoscope rotation mechanism are located in a same housing 309. This housing is connected to the gimbals that slide in the arc. A spring is connected to the gimbals at one end and to the mechanisms housing at the other end not allowing the housing to move down. A wire is also connected to the gimbals at one end and to the mechanisms housing at the other end keeping a desired distance between the gimbals and the housing.

[0108] These mechanisms may be operated by flexible shaft that are coupled to the motors located in the motor box, or by motors attached directly to the mechanisms axles.

The Endoscope Rotation Mechanism

[0109] A flexible shaft couples a motor located in motor box to an axle of a worm gear which rotating a cog wheel. The aforesaid cog wheel has a centered passage for a proximal portion of the endoscope. A locking sub-mechanism (not shown) is adapted to fixate and release the endoscope 307.

The Zoom Mechanism

[0110] A flexible shaft is connected to an axle of a worm gear. During zoom down the drum mechanically connected to the worm gear winds the wire up, so that the distance between the drum and the muff becomes shorter. When the motor stops moving, the spring keeps tension of the wire. The structure of the worm gear prevents the spring 185 from unsanctioned displacement of the transmission box. During zoom out movement the motor rotates in the opposite direction. The unwrapped wire lets the spring to extend. As a result the zoom box transmission rises.

[0111] The spring may be a part of the Telescopic Guide shown in FIGS. 3e, 5, 6.

[0112] Reference is made now to FIG. 3 illustrating a cut view of the first part. Rotating the lead screw cause the linear movement of the moving nut. In the case where the moving nut 10 moves forward, it pushes the chain of links 20 that are connected to gimbal. The link movement is guided by tiny wheels that are placed in the curved guide way 40. The

movement of the link is passed to the outer gimbal **50** directly via a connector **60** or like in FIG. **2** via another link **20**. There is no principal limit to number of links except the physical dimensions of the mechanism.

[0113] Reference is now made to FIG. **3a** which schematically illustrate the camera holder which additionally comprises sterilizes sleeve **131** which covers the camera **308**.

[0114] Reference is made now to FIG. **3b** illustrating different view of the entire mechanism. FIG. **3c** additionally displays telescopic guide **55** in its stretched position.

[0115] Reference is made now to FIG. **4** illustrating another realization of the mechanism using only one curved guide way **311**, and a single chain of links **312**. This structure has some more advantages: the whole mechanism is thinner and tinier and allows a faster connection and disconnection of the endoscope from the mechanism, for example in a case when cleaning of the endoscope lens is needed.

[0116] Reference is made now to FIG. **5** illustrating the mechanism's four degrees of freedom: rotation **e1** (provided by the rotating DF), rotation **e2** (provided by the sliding DF), rotation about **e3** (provided by endoscope rotation mechanism) and zoom along **e3**.

[0117] Reference is made now to FIGS. **6** and **7**, illustrating the mechanism of the telescopic guide **55**. The telescopic guide mechanism enables the movement of the endoscope to move in "a zoom movement", where the endoscope moves along its longitudinal axis. Reference is made now to FIG. **6**. FIG. **6** illustrates the connection between the housing **309** and the arc mechanism (shown for example in FIG. **3**). The telescopic guide **55** connects the housing **309** to the inner gimbal **62**. As explained before the gimbal slides along the arc, also the gimbal moves with the arc, when the arc rotates from side to side. While keeping a rigid connection with the inner gimbal **62**, the telescopic guide enables the movement of the endoscope **307** in a zoom movement, where the endoscope moves along its longitudinal axis.

[0118] The endoscope **307** is locked in housing **309** and passes through the inner gimbal **62**.

[0119] A quick release handle **61** adapted to disassemble said endoscope out of said housing **309** without changing any of said degrees of freedom.

[0120] The zoom mechanism components are explained in FIG. **7**.

[0121] FIG. **7** shows the components of the zoom mechanism. Worm **1** (denotes as **71**) that may be rotate clockwise or counter clockwise, by a flexible shaft (not shown in this figure—**303** in FIG. **8**) or directly by tiny motor. When worm **1** rotates it rotates also cog wheel **1** (denotes as **72**).

[0122] Cog wheel **1** (denotes as **72**) have the same axle with drum **1** (denotes as **73**), when cog wheel **1** rotates, drum **1** rotates also and winds or unwinds (depends on the direction of the rotation) the wire **75** that is wrapped around the drum.

[0123] When the rotation of the results unwinding of the wire, spring **185** contained in the telescopic guide **55** expands and pushes the housing up, increasing the distance between the gimbal **62** and the housing **309** resulting "zoom out" movement.

[0124] When the rotation of the results winding, shortening the distance between the gimbal **62** and the housing **309** resulting "zoom in" movement.

[0125] FIG. **7** also shows the components of the mechanism that rotates the endoscope around its longitudinal axis. This mechanism comprises of worm **2** (denotes as **76**) and cog wheel **2** (denotes as **77**).

[0126] Worm **2** (denotes as **76**) that may be rotate clockwise or counter clockwise, by a flexible shaft (not shown in this figure—**303** in FIG. **8**) or directly by tiny motor. When worm **2** (denotes as **76**) rotates it rotates also cog wheel **2** (denotes as **77**). In one embodiment of this invention cog wheel may be attached directly to the endoscope, by the force of friction. When cog wheel **2** (denotes as **77**) rotates the endoscope rotates also in the same directions.

[0127] In another embodiment of this invention, as shown in FIG. **28b**, cog wheel **2** (denotes as **77**) may rotate via pin that passes through a hole in a ring that is attached directly to the endoscope, by the force of friction. When cog wheel **2** (**77**) rotates, the ring rotates and the endoscope rotates also in the same directions.

[0128] Reference is made now to FIGS. **8a**, **8b**, **8c** illustrating an example of a camera holder mechanism for laparoscopic surgery. The camera holder comprises a motor house **301** and a zoom and rotation mechanism **309**, a sliding DF, a rotating DF, arms for polling the slider (**300**) and tubes with flexible wire that transmit the rotation moment to the component of the zoom mechanism (**303**).

[0129] The present invention generally relates to means and methods of controlling an endoscope system for laparoscopic surgery, in which the endoscope (into which a camera **308** is coupled) is inserted through a small incision in the abdomen as illustrated in FIG. **9**.

[0130] It is another object of the present invention to present a novel means for controlling the spatial position of endoscope tube in laparoscopic surgery. The present device is cheap, easily install and disassemble, comfortable to use, not limiting the dexterity of the surgeon and having small physical dimension.

[0131] The small size of present invention is achieved by applying the following steps:

[0132] 1. separating the moving parts from the motors and transmitting the motor power by cable and/or shafts means;

[0133] 2. applying a linear zoom mechanism, allowing a full range zoom action, independent of other moving parts in the mechanism, e.g. not like other robots that achieve the linear zoom action, by a combined movement of the robot arms;

[0134] 3. obtaining a rotational mechanism that rotates the endoscope about its long axis, independently of other moving parts of the mechanism, e.g., not like other robots that does not have the ability to compensate uni wanted rotational movements (for example LER), or by a combined movement of the robot arms that produce big movements in order to achieve small rotations (AESOP Endoassist LapMan).

[0135] Reference is now made to FIG. **10** which schematically represent the entire system according to one embodiment of the present invention. According to that embodiment, the system comprises three main parts:

[0136] a manipulating endoscope mechanism (**1**); a force carriage system (**2**); and a force source (**3**). The manipulating endoscope mechanism may comprise cables, springs and

rods. The force carriage system may comprise cables, chains, rods. The force source comprises motors or/and may comprise actuators and pistons.

[0137] Reference is made now to FIG. 11, presenting a schematic illustration of the camera holder according to another embodiment of the present invention. The camera holder comprises a zoom ring 1; zoom mechanism 2; orientation ring 3; three cables, 4a, 4b and 4c having length of L_1 , L_2 and L_3 respectively; a spring 5; and a basis ring 6. 7 describes the pinhole in the operated body. When the lengths of L_1 and L_2 are changed in conjunction with the spring resistance, the orientation ring is moved relatively to the basis ring and get to an equilibrium point as illustrated in FIG. 12. Although a zoom action can be obtained by coordinated shortening of the cables L_1 , L_2 and L_3 the mechanism includes an additional zoom option that acts independently of cable lengths L_1 , L_2 and L_3 .

[0138] The different lengths of the cables when tensed, fix the place of the orientation ring as illustrated in FIG. 13. The mechanism controlling the cables length allows a shifting of the orientation cable and an inclination of the endoscope to a wanted angle. The endoscope has to rotate around its length axis whereas the surgeon operates without changing the orientation.

[0139] FIG. 14 schematically displays an “adjustment cable” zoom mechanism 1400 according to one embodiment of the present invention (alternative zoom mechanisms are displayed in FIGS. 18a, 18b, 19a, 19b, 20, 23 and 27). The zoom action is the endoscope movement in front and backward without changing the orientation. As can be seen from FIG. 14 the zoom mechanism additionally comprises an adjustment cable 141, 4 closed bar linkage R1, R2, R3, R4 with the pivots $P_{1,2}$, $P_{2,3}$, $P_{3,4}$, $P_{1,4}$ with a linear spring containing the adjustment cable with a first end at pivot $P_{1,4}$ and the second end at pivot $P_{2,3}$.

[0140] The couple Spring 142 and the adjustment cable determines the distance between pivots $P_{1,2}$ and $P_{1,4}$ hence determines the Zoom position of the endoscope.

[0141] Reference is made now to FIG. 15 presenting a schematic description of the rotation mechanism. As can be seen from FIG. 15, a rotating cable 151 is coupled to a worm gear 152 which is connected to the endoscope ring. When the cable rotates the worm gear 152, the cog which is connected to the endoscope ring 153, rotates and the endoscope passing through and rotates at the same amount.

[0142] Reference is made now to the portable feature of the camera holder as described in FIG. 16. As shown in FIG. 16 the camera holder additionally comprises an adjustable arm 161 and a basis 162 including motors. The mechanism can be placed beside a bed using a track 171, as described in FIG. 17.

[0143] Reference is now made to FIGS. 18a, 18b, 19a, 19b, and 20 which display different zoom mechanisms:

- (1) “parallelogram rods mechanism” (see FIG. 18a, 18b);
- (2) “a spring mechanism”. The spring connects the ring zoom and the orientation ring mechanism (see FIGS. 19a, 19b); and
- (3) a “reduction force mechanism” (see FIG. 20).

[0144] A tiny motor wraps the Z cable. The stake system allows on one hand a reduction of the required force that compress the spring, and on the other hand an augmentation

of the zoom movement sensibility. In order to obtain a small zoom movement, many windings are required.

[0145] Reference is now made to FIGS. 18a and 18b which schematically display the zoom mechanism according to the “parallelogram rods mechanism”.

[0146] As can be seen from FIGS. 18a and 18b the zoom mechanism comprises parallelogram rods 25, a spring 22, zoom ring 21, orientation ring 23 and a driving z cable 20.

[0147] At the first stage (FIG. 18a), the spring 22 is compress. When the Z cable 20 is pulled the compressed spring 22 is released (see FIG. 18b) and the distance between the zoom ring 21 and the orientation ring 23 is reduced. In this manner the zoom movement is produced and the endoscope 307 is moved from position h_0 to position h_1 . Releasing and pulling the driving Z cable 20 allows continually the deep fixing of the zoom.

[0148] Reference is now made to FIGS. 19a and 19b which schematically display another zoom mechanism—“a spring mechanism”. As can be seen from FIGS. 19a and 19b the zoom mechanism comprises a ring zoom 21, an orientation ring 23 and a spring 24 which connects the ring zoom 21 and the orientation ring 23.

[0149] When the z-cable 20 is pulled spring 24 is compressed (as can be seen in FIG. 19b) and the distance between the ring zoom 21 and the orientation ring 23 is reduced.

[0150] Reference is now made to FIG. 20 which schematically display another zoom mechanism—“reduction force mechanisms”. As can be seen from FIG. 20, the zoom mechanism comprises a motor 27, a ring zoom 21, an orientation ring 23 and a reduction force device 28 which connects the ring zoom 21 and the orientation ring 23.

[0151] Reference is now made to FIGS. 21 and 22 which display another alternative to change the cable's length. According to FIGS. 21 and 22 another alternative is to base the cable length change is on pulley blocks 70 motion. The pulley blocks are located on the endoscope motion mechanism. FIG. 21 presents a schematic section view of this. The pulley block 70 contains a drum with an axle and a wire. The pulley block may be operated by any kind of shaft rigid or flexible. This kind of structure demonstrates another embodiment using the same principle: controlling the spatial angular position of the endoscope by using a combination of the wires lengths. The pulley block may have some advantages in respect to the mechanisms of wrapping the wires that pass through the adjusting arm as described before.

[0152] In FIG. 22, a three-dimension description is proposed, showing also the wire 80 that activates the rotation mechanism.

[0153] Reference is now made to FIG. 23 which display the “rotating cable” zoom mechanism. Realization of the zoom mechanism can be done by rotating cable which turns a central screw comprised of two different screws with an opposite direction: screw R 231 and screw L 232 when the central zoom is rotated to a first direction; say clockwise the nuts become closer and the endoscope moves in a zoom up movement. When the central zoom is rotated to a second direction, counterclockwise the distance between the nuts increase and the endoscope moves in a zoom down movement as illustrated in FIG. 23.

[0154] Reference is made now to FIGS. 24 and 25, presenting a schematic and illustrated drawing of the entire device according to another embodiment of the present invention. As can be seen from FIG. 24 the device comprises inter alia a manipulating endoscope mechanism (1); a force carriage system (2); and a manipulating system actuator or a force source (3). FIG. 25 presents a schematic illustration of the manipulating endoscope mechanism (1). The mechanism comprises inter alia from a rotating link (12); linear links (11a, b, c, d); gimbals ring mechanism (14); zoom leading bars (15); zoom and rotation endoscope mechanism (16); cables tubes (13). The pinhole in the operated body is illustrated by 7, where the endoscope 4 passes through into the abdomen cavity.

[0155] Reference is made now to FIG. 26, presenting a schematic cut view along the sliding links 11a,b,c. The cable head 17 is mounted in a hole at the head of link 11a. When the links 11a is pulled by cable 18 it slide into links 11b against the pushing force of springs 19a, b and therefore the distance between the center of the gimbals 14 and the center of the rotating link 12 becomes shorter. When the cable 18 is released, spring 19a push links 11a out of links 11b and 11b out of links 11c, and the distance between the center of the gimbals 14 and the center of the rotating link 12 becomes longer, in both cases the gimbals is moved relatively to the pinhole and changes the orientation of the endoscope. When the cable does not move, equilibrium is kept at every point by the pushing forces of the springs that tend to push the link outward, and the cable tension. The zoom action is essential in laparoscopic surgery. Changing the zoom enables the surgeon to see important details of the operated organs e.g. "zoom in", and to examine the general situation of the operation status when moving the endoscope away from the scenery e.g. "zoom out". Another important feature is the ability to make a zoom movement while keeping the center of the picture without movement. This could be achieved if the zoom movement is done without changing the endoscope orientation.

[0156] Reference is made now to FIG. 27, presenting the two springs zoom mechanism (270), fulfilling the needs mentioned above. The zoom action is the endoscope movement into (zoom in) and out of the abdomen cavity (zoom out), without changing the endoscope orientation. The "zoom in" action is obtained by shortening cable 16a, and the "zoom out" action is obtained by extending the length of cable 16a. The springs 19a and 19b tend to increase the angle between the pair of links 15a 15b, and the pair 15c 15d and so to produce the "zoom out" movement. The length of cable 16a determines the amount of the "zoom in". When the endoscope does not move, there is equilibrium between the springs force and the cable tension. Box 16 contains two separate mechanisms that control the linear movement of the endoscope e.g. "zoom in", "zoom out" and the rotation angle of the endoscope along the long axis.

[0157] Reference is made now to FIGS. 28a, 28b and 28c presenting schematically another principle mechanism that controls the linear movement of the endoscope e.g. "zoom in", and "zoom out".

[0158] The ability to rotate along the endoscope long axis is essential in laparoscopic surgery. While rotating the endoscope through the insertion point 7 in order to change the endoscope orientation e.g. combination of angle α and

angle β shown at FIG. 29, a component of the angular change may be not along the long axis of the endoscope. This angular component may cause undesirable rotation of the endoscope, which in result, cause annoying rotating movement of the picture as viewed on the surgeon's video screen. In a traditional laparoscopic operation, the person that holds the endoscope, intuitively, makes the needed changes to keep the operation scenery without un desirable rotation e.g., keeping the moving picture parallel to it self at all time.

[0159] FIGS. 28a, 28b and FIG. 28c present the rotation mechanism (80), filling the needs mentioned above, and also allowing fast removal of the endoscope in order to clean its lens. The cog-wheel 163 allows the endoscope rod 307 to cross through its center and to make roll and sliding movements. The peg 164 arises from cog-wheel 163 upper surface. A disk 165 is tightened to the endoscope rod 4. While assembling the endoscope, the upper wall of the box 16 is opened and the endoscope is entered through cog-wheel 163 center, into a hole in the lower wall and through ring e.g. gimbals 14 until the peg 164 is threaded into aperture 166 of disk 165. Then the upper wall of box 16 is closed, keeping the endoscope from moving out or box 16, to ensure coupling between the endoscope and the entire zoom mechanism. The rotation of the endoscope along is achieved by rotating the screw 162 that moves cog-wheel 163 and the endoscope 307 via coupled disk 165. The source of the movement of screw 162 can be a rotating cable transmitting the rotation movement from "remote" motor or small motor placed in or near box 16. When needed, the mechanism described above allows quick disassembling of the endoscope out of the zoom mechanism without changing any degree of freedom of its spatial position. This property is important because the surgeon does not have to deal with re-positioning of the system. This property is achieved because the endoscope 307 does not have any role in keeping the position of the entire zoom mechanism. The equilibrium between links 15, springs 19 and cable 16a maintain depth of the zoom and constrain of relation between the peg 164 and hole 166 keeps the angle of rotation. When the endoscope is assembled again, the endoscope retrieves its original spatial position.

[0160] While executing the operation the surgeon must be able to move the endoscope to any desired orientation. The envelope of the endoscope range of movement is shown in FIG. 29.

[0161] Reference is made now to FIG. 30, presenting schematically the way the mechanism acts to controls one angle of the endoscope by changing the total length of the telescopic arm. FIG. 30 shows the angular movement of endoscope 307 that was at starting position P0 e.g. $\alpha=0$. Activating the sliding mechanism causes the movement of gimbals rings 14 from point A to point B causing endoscope 4 to rotate about the insertion point 70, to a desired position P1. While the combined shortening of links 11 a, b, c, the distance between gimbals 14 and the insertion point 7 changes, causing an undesired zoom movement. The distance of this movement can be calculated and compensated by a controlled zoom motion.

[0162] Reference is made now to FIG. 31, schematically presenting the way the mechanism acts to controls another angle e.g. β of the endoscope by rotating telescopic arms

FIG. 31 shows the angular movement of endoscope 307 that was at starting position P_0 . Activating the rotating mechanism causes the movement of gimbals rings 14 in a radial movement, from point A to point B e.g. angle Ψ , causing endoscope 307 to rotate about the insertion point 7, by angle β , to a desired position P1. While the rotating of arm 1, the distance between gimbals 14 and the insertion point 7 changes, causing an undesired zoom movement. The distance of this movement can be calculated and compensated by a controlled zoom motion. The combination of the two independent movements of the mechanism arm enables the surgeon to move the endoscope to any orientation, and reach any desired point within the working envelope.

[0163] Reference is made now to the portable feature of the mechanism as described in FIG. 32a. The mechanism is placed beside a bed, on track 201, and can be placed at any point along track 201 by moving slider 202; in order to achieve the necessary position the surgeon can also rotate the system around pivot 203 and to change the height by sliding the system along house 204. FIG. 32b shows schematically from upper view, the position abilities of the system: the rotation angle γ , and the horizontal position X slider.

1. A camera holder, useful for laparoscopic surgery; wherein said camera holder is provided with means of manipulation in four degrees of freedom; further wherein said camera holder is provided with means of controlling the spatial position of an endoscope tube to any orientation during said laparoscopic surgery, such that said endoscope reaches any desired area within the working envelope in an operated body.

2. The camera holder according to claim 1, wherein said camera holder is adapted to have small physical dimension.

3. The camera holder according to claim 2, wherein said camera holder comprises:

- a. a housing (309); said housing is adapted to be connected and disconnected to said endoscope; said housing comprises:
 - i. at least one zoom mechanism;
 - ii. at least one endoscope rotation mechanisms;
- b. rotating DF (304); and
- c. sliding DF (305).

4. The camera holder according to claim 3, wherein said camera holder additionally comprising:

- a. motor house;
- b. means adapted to transmit movement to said zoom mechanism;
- c. means adapted to transmit movement to said endoscope rotation mechanism;
- d. means adapted to transmit movements to said endoscope rotating DF;
- e. means adapted to transmit movements to the sliding DF.

5. The camera holder according to claim 4, wherein said camera holder is disposable.

6. The camera holder according to claim 4, wherein said camera holder additionally comprises a quick release handle adapted to disassemble said endoscope out of said housing without changing any of said degrees of freedom.

7. The camera holder according to claim 4, wherein said camera holder additionally comprising a telescopic guide; said telescopic guide is adapted to provide said endoscope movement along said endoscope longitudinal axis.

8. The camera holder mechanism according claim 4, additionally comprising:

- a. a zoom ring (1);
- b. orientation ring (3);
- c. at least two cables 4a and 4b; said cables 4a and 4b are characterized by having length of L_1 and L_2 ;
- d. a spring (5); said spring is characterized by having a resistance K; and
- e. a basis ring (6);

wherein lengths of L_1 , L_2 are changeable in conjunction with said spring's resistance K, thereby said orientation ring is moved relatively to said basis ring.

9. The camera holder according to claim 4, wherein said rotation mechanism comprises at least one cable; at least one worm gear; said cable is adapted to rotate said worm gear such that said endoscope is rotated.

10. The camera holder according to claim 4, wherein said rotation mechanism comprises at least one pulley block; said pulley block are adapted to control the spatial angular position of said endoscope.

11. The camera holder according to claim 4, wherein said camera holder additionally comprising means such that said camera holder is adapted to be portable.

12. The camera holder according to claim 11, wherein said means comprising (a) at least one adjustable arm; and (b) a basis comprising at least one motor; said adjustable arm couples said camera holder and said basis.

13. The camera holder according to claim 4, wherein said zoom mechanism is selected from a group comprising adjustment cable mechanism, parallelogram rods mechanism, a spring mechanism, a reduction force mechanism, rotating cable mechanism and a two springs zoom mechanism.

14. The camera holder mechanism according to claim 1, wherein said camera holder comprising a manipulating endoscope mechanism (1); a force carriage system (2); and a force source (3).

15. The camera holder mechanism according to claim 14, wherein said manipulating endoscope mechanism comprises:

- a. at least one cable;
 - b. at least one spring; and
 - c. at least one rod;
- said force carriage system comprises:
- a. at least one cable;
 - b. at least one chain; and
 - c. at least one rod;
- said force source comprises

- a. at least one motor; and/or at least one actuator; at least one piston.

16. A method for controlling the spatial position of endoscope tube to any orientation in laparoscopic surgery,

such that the surgeon reaches any desired area within the working envelope in operated body; said method comprising the step of:

- a. obtaining a camera holder according to claim 4;
- b. assembling said endoscope to said housing; and
- c. controlling and manipulating said endoscope;

wherein said step of controlling and manipulating said endoscope is providing said endoscope movement in four degrees of freedom.

17. The method according to claim 16, additionally comprising the step of zooming in and/or zooming out of said desired area such that more precisions is obtained.

18. The method according to claim 17, wherein said step of zooming in and/or zooming out additionally comprises the step of moving said endoscope along said endoscope longitudinal axis.

19. The method according to claim 16, additionally comprising the step of rotating said endoscope.

20. The method according to claim 16, additionally comprising the step of disassembling said endoscope to said housing.

21. The method according to claim 16, additionally comprising the step of controlling the rotation angle of said endoscope along said endoscope long axis.

22. The method according to claim 16, additionally comprising the step of selecting said zoom mechanism from a group comprising adjustment cable mechanism, parallelogram rods mechanism, a spring mechanism, a reduction force mechanism, rotating cable mechanism and a two springs zoom mechanism.

23. The method according to claim 16, additionally comprising the step of adjusting said camera holder to be portable.

24. The method according to claim 16, additionally comprising the step of disassembling the endoscope out of the zoom mechanism without changing any degree of freedom of the spatial position of said endoscope, by activating said endoscope independently of other moving parts of the mechanism, such that the entire system does not have to be re-positioned.

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摘要(译)

用于腹腔镜手术的外科医生和内窥镜系统之间的改进的界面，保持腹腔镜来和/或控制自动内窥镜助手包括至少一个具有至少一个操作键的无线发射器（12a）。至少一个无线接收器（11），至少一个装有传统手术器械空间定位软件的传统腹腔镜计算机化系统（15），以及传统的自动辅助操纵软件，加载到传统腹腔镜系统上的软件，能够对视觉响应进行按下无线发射器上的至少一个按键以及与传统的自动辅助操纵软件的接口以便实现内窥镜的移动，以及至少一个视频屏幕（30）。

