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- (81) **Designated States** (*unless otherwise indicated, for every kind of national protection available*): AE, AG, AL, AM, AO, AT, AU, AZ, BA, BB, BG, BH, BN, BR, BW, BY, BZ, CA, CH, CL, CN, CO, CR, CU, CZ, DE, DJ, DK, DM, DO, DZ, EC, EE, EG, ES, FI, GB, GD, GE, GH, GM, GT, HN, HR, HU, ID, IL, IN, IR, IS, JP, KE, KG, KH, KN, KP, KR, KW, KZ, LA, LC, LK, LR, LS, LU, LY, MA, MD, ME, MG, MK, MN, MW, MX, MY, MZ, NA, NG, NI, NO, NZ, OM, PA, PE, PG, PH, PL, PT, QA, RO, RS, RU, RW, SA, SC, SD, SE, SG, SK, SL, SM, ST, SV, SY, TH, TJ, TM, TN, TR, TT, TZ, UA, UG, US, UZ, VC, VN, ZA, ZM, ZW.
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(54) **Title:** CANNULA ASSEMBLIES FOR USE WITH ROBOTIC SURGICAL SYSTEMS

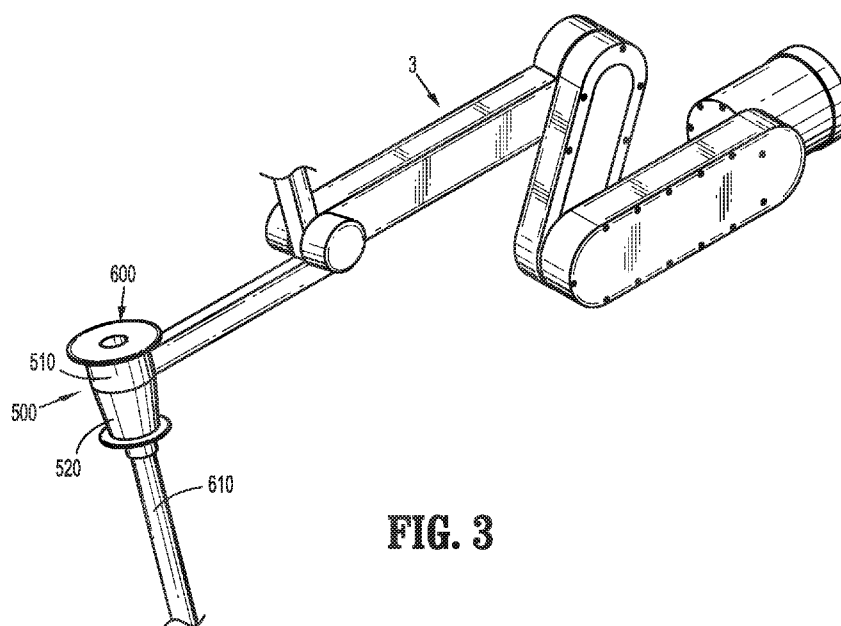


FIG. 3

(57) **Abstract:** The present disclosure relates to cannula assemblies for use with robotic surgical systems. According to an aspect of the present disclosure, a surgical cannula assembly for use with a mounting structure of a robotic arm, is provided. The surgical cannula assembly includes a cannula configured for reception of a surgical instrument at least partially therethrough; an attachment mechanism configured to releasably engage the cannula; and a barrier configured to extend through a channel of the mounting structure. The barrier includes a proximal ring for positioning adjacent a proximal face of the mounting structure, a distal ring for positioning adjacent a distal face of the mounting structure, and a cylindrical section defining a lumen therein and extending between the proximal ring and the distal ring, the cannula configured for insertion within the lumen in a distal -to-proximal direction.



TM), European (AL, AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI, FR, GB, GR, HR, HU, IE, IS, IT, LT, LU, LV, MC, MK, MT, NL, NO, PL, PT, RO, RS, SE, SI, SK, SM, TR), OAPI (BF, BJ, CF, CG, CI, CM, GA, GN, GQ, GW, KM, ML, MR, NE, SN, TD, TG).

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CANNULA ASSEMBLIES FOR USE WITH ROBOTIC SURGICAL SYSTEMS

CROSS-REFERENCE TO RELATED APPLICATION

[0001] The present application claims the benefit of and priority to U.S. Provisional Patent Application Serial No. 62/341,888, filed on May 26, 2016, the entire contents of which being hereby incorporated by reference in its entirety.

BACKGROUND

[0002] Robotic surgical systems have been used in minimally invasive medical procedures. Some robotic surgical systems include a console supporting a robot arm, and at least one elongated surgical instrument including an end effector such as a forceps or a grasping tool that is mounted to the robot arm via a wrist assembly. During a medical procedure, part of the elongated surgical instrument (e.g., the end effector) is typically inserted into a small incision (via a cannula assembly) or a natural orifice of a patient to position the end effector at a work site within the body of the patient. Moreover, robotic surgical systems may include a first robot arm and mounting structure for supporting an elongated surgical instrument, and at least a second robot arm and mounting structure for supporting a cannula assembly.

[0003] Cables extend from the robot console, through the robot arm, and connect to the wrist assembly and/or end effector. In some instances, the cables are actuated by means of motors that are controlled by a processing system including a user interface for a surgeon or clinician to be able to control the robotic surgical system including the robot arm, the mounting structure and/or the end effector.

[0004] It is often desired to re-use parts of the robotic system. As such, it may be important to ensure the sterility of such re-usable components of the robotic system. Accordingly, there is a need to provide a sterile barrier between a cannula of the cannula assembly and the mounting structure associated therewith. It may also be desirable to have the ability to load the cannula into the associated mounting structure in a distal-to-proximal direction to avoid awkwardly lifting the cannula and loading it proximally-to-distally through the mounting structure.

SUMMARY

[0005] The present disclosure relates to cannula assemblies for use with robotic surgical systems. According to an aspect of the present disclosure, a surgical cannula assembly for use with a mounting structure of a robotic arm, is provided. The surgical cannula assembly includes a cannula configured for reception of a surgical instrument at least partially therethrough; an attachment mechanism configured to releasably engage the cannula; and a barrier configured to extend through a channel of the mounting structure. The barrier includes a proximal ring for positioning adjacent a proximal face of the mounting structure, a distal ring for positioning adjacent a distal face of the mounting structure, and a cylindrical section defining a lumen therein and extending between the proximal ring and the distal ring, the cannula configured for insertion within the lumen in a distal-to-proximal direction.

[0006] The barrier may be configured to provide a sterile barrier between the cannula and the mounting structure during use.

[0007] The surgical cannula assembly may further include a first seal disposed within the lumen of the barrier and being configured to provide an air-tight seal about a surgical instrument that is inserted through a hole defined by the first seal.

[0008] The surgical cannula assembly may further include a second seal disposed within the lumen of the barrier and being configured to provide an air-tight seal within the lumen of the barrier in the absence of a surgical instrument within the lumen of the barrier.

[0009] The first seal and the second seal may be made from the same material as the barrier.

[00010] The cannula may be configured for removal from the lumen of the barrier in a proximal-to-distal direction.

[00011] The cannula may be configured for removal from the lumen in a distal-to-proximal direction.

[00012] According to a further aspect of the present disclosure, a method of engaging a cannula with a mounting structure of a robotic arm is provided. The method includes inserting a portion of a cannula within a channel of the mounting structure in a distal-to-proximal direction, the cannula providing a path through which a surgical instrument can be inserted in a proximal-to-distal direction at least partially therethrough to access a patient.

[00013] The method may further include removing the cannula from engagement with the mounting structure in a proximal-to-distal direction.

[00014] The method may also include inserting a barrier at least partially within the channel of the mounting structure.

[00015] The method may further include engaging an attachment member with the barrier, and removably securing the attachment member to the cannula.

[00016] The method may also include removing the cannula from engagement with the mounting structure in a distal-to-proximal direction.

BRIEF DESCRIPTION OF THE DRAWINGS

[00017] Embodiments of the present disclosure are described herein with reference to the accompanying drawings, wherein:

[00018] FIG. 1A is a schematic illustration of a medical work station and operating console in accordance with the present disclosure;

[00019] FIG. 1B is a schematic, perspective view of a motor of a control device of the medical work station of FIG. 1A;

[00020] FIG. 2 is a perspective view of an arm of the medical work station of FIGS. 1A and 1B including a mounting structure thereon;

[00021] FIG. 3 is a perspective view of the arm and mounting structure of FIG. 2 including a cannula assembly extending through the mounting structure;

[00022] FIG. 4 is a perspective view of the mounting structure and cannula assembly of FIG. 3; and

[00023] FIG. 5 is a cross-sectional view of the mounting structure and cannula assembly of FIGS. 3 and 4.

DETAILED DESCRIPTION

[00024] Embodiments of the presently disclosed robotic surgical systems and cannula assemblies are described in detail with reference to the drawings, in which like reference numerals designate identical or corresponding elements in each of the several views. As used herein the term “distal” refers to that portion of the system or assembly that is farther from the user, while the term “proximal” refers to that portion of the system or assembly that is closer to the user.

[00025] Referring initially to FIGS. 1A and 1B, a medical work station is shown generally as work station 1 and generally includes a plurality of robot arms 2, 3; a control device 4; and an operating console 5 coupled with control device 4. Operating console 5 includes a display device 6, which is set up in particular to display three-dimensional images; and manual input devices 7, 8, by means of which a person (not shown), for example a surgeon, is able to telemanipulate robot arms 2, 3 in a first operating mode, as known in principle to a person skilled in the art.

[00026] Each of the robot arms 2, 3 includes a plurality of members, which are connected through joints, and an instrument control unit 100 or a mounting structure 500. Instrument control unit 100 may be attached, for example, to a surgical instrument 10 having an instrument drive assembly 200, and supporting an end effector 20 having jaw members. Mounting structure 500 may be configured to slidably accept, for example, a cannula assembly 600, as will be described in greater detail below.

[00027] Robot arms 2, 3 may be driven by electric drives (not shown) that are connected to control device 4. Control device 4 (e.g., a computer) is set up to activate the drives, in particular by means of a computer program, in such a way that robot arms 2, 3, instrument control units 100 (and thus the surgical instruments 10), and mounting structure 500 (and thus the cannula assembly 600) execute a desired movement according to a movement defined by means of manual input devices 7, 8. Control device 4 may also be set up in such a way that it regulates the movement of robot arms 2, 3 and/or of the drives.

[00028] Medical work station 1 is configured for use on a patient 13 lying on a patient table 12 to be treated in a minimally invasive manner by means of surgical instrument 10. Medical work station 1 may also include more than two robot arms 2, 3, the additional robot arms likewise being connected to control device 4 and being telemanipulatable by means of operating console 5. An instrument control unit, a surgical instrument, a mounting structure and/or a cannula assembly may also be attached or coupled to the additional robot arms. Medical work station 1 may include a database 14, in particular coupled to with control device 4, in which are stored for example pre-operative data from patient 13 and/or anatomical atlases.

[00029] Reference may be made to U.S. Patent No. 8,828,023, entitled “Medical Workstation,” the entire content of which is incorporated herein by reference, for a detailed discussion of the construction and operation of medical work station 1.

[00030] Control device 4 may control a plurality of motors (e.g., “M1” – “M6”). Motors may be part of instrument control unit 100 and/or disposed externally of instrument control unit 100. Motors “M” (e.g., motors “M” being located externally of instrument control unit 100) may be configured to rotate a crown gear “CG” (FIG. 1B), or the like, that is keyed to or non-

rotatably supported on a rotatable shaft of at least some of motors “M.” In use, as motors “M” are driven, the rotation of crown gear(s) “CG” effects operation and/or movement of instrument drive assembly 200 of surgical instrument 10, as discussed below. It is further envisioned that at least one motor “M” receives signals wirelessly (e.g., from control device 4). It is contemplated that control device 4 coordinates the activation of the various motors (Motor 1...n) to coordinate an operation and/or movement of surgical instrument 10 and/or cannula assembly 600. It is envisioned that each motor corresponds to a separate degree of freedom of surgical instrument 10 engaged with instrument control unit 100. It is further envisioned that more than one motor, including every motor (Motor 1...n), is used for each degree of freedom. Reference may be made to commonly owned International Patent Publication No. WO 2015/088647, filed on October 20, 2014, entitled “Wrist and Jaw Assemblies for Robotic Surgical Systems,” the entire content of which is incorporated herein by reference, for a detailed discussion of illustrative examples of the construction and operation of end effectors 20 for use with instrument control unit 100.

[00031] Turning now to FIGS. 2-3, robot arm 3 is shown supporting mounting structure 500. It is envisioned that mounting structure 500 is removably or fixedly coupled to robot arm 3. It is further envisioned that a portion (e.g., a proximal housing 510) of mounting structure 500 is rotatable with respect to another portion (e.g., a distal housing 520) of mounting structure 500, such that at least a portion of mounting structure 500 is rotatable with respect to robot arm 3. As discussed in further detail below, mounting structure 500 is configured to accept cannula assembly 600 at least partially therein. For example, at least a portion of cannula assembly 600 may be inserted through a channel 530 extending through mounting structure 500 in the general direction of arrow “A” in FIG. 3, from a distal direction toward a proximal direction.

[00032] Additionally, a conventional access port is usable with cannula assembly 600 (e.g., in embodiments using medical work station 10 in FIG. 1A). In such uses, alignment between the robotic arm 3 and the access port is maintained, thereby removing the need to simultaneously align the surgical instrument 10 with the robot arm 3 and align the surgical instrument 10 with the access port.

[00033] Referring to FIGS. 4 and 5, cannula assembly 600 is shown extending through mounting structure 500. Cannula assembly 600 includes a cannula or trocar 610, an attachment member 620, a barrier 630, a first seal 640, and a second seal 650. Generally, cannula assembly 600 is configured to provide a passageway for a surgical instrument (e.g., surgical instrument 10) to be inserted through an incision in a patient's skin and adjacent target tissue. Additionally, as discussed in further detail below, cannula assembly 600 is configured to minimize or prevent gasses and/or fluids from exiting the patient proximally through cannula assembly 600, for example.

[00034] Cannula 610 is an elongated, hollow tube that is configured to allow an elongated portion and an end effector of a surgical instrument to pass therethrough and access target tissue within a patient, for example. Cannula 610 is sized and dimensioned for insertion within a channel 530 of mounting structure 500. More particularly, cannula 610 is configured to be inserted into channel 530 of mounting structure 500 in a distal-to-proximal direction (in the general direction of arrow "B" in FIG. 5), and cannula 610 may be removed from channel 530 in a proximal-to-distal direction (in the general direction of arrow "C" in FIG. 5). An outer diameter of cannula 610 and an inner diameter of barrier 630 (e.g., a distal cylindrical section 636) within channel 530 of mounting structure 500 may be similarly sized to enable a frictional engagement therebetween.

[00035] With continued reference to FIGS. 4 and 5, attachment member 620 is a ring-like, cylindrical tube including a longitudinal cavity 622 extending therethrough, and including a proximal recess 624 therein. As shown in FIG. 5, cannula 610 is sized and dimensioned to extend through longitudinal cavity 622 of attachment member 620. More particularly, the present disclosure envisions that cannula 610 is fixedly attached to attachment member 620, is frictionally engaged with attachment member 620, or is mechanically fastened or able to be fastened to attachment member 620. For instance, it is envisioned that attachment member 620 engages cannula 610 with mechanical structure such as a set screw 629 (as shown in FIG. 5), break-away snaps (not explicitly shown), ribs designed to fracture in response to a predetermined amount of force (not explicitly shown), a bayonet-type connection, etc. It is further envisioned that the engagement between attachment member 620 and cannula 610 allows cannula 610 to be removed from mounting structure 500 in a distal-to-proximal direction (in the general direction of arrow "B" in FIG. 5), such that cannula 610 can be removed from mounting structure 500 in either a distal-to-proximal direction or a proximal-to-distal direction. For instance, attachment member 620 may be removed from cannula 610, e.g., by loosening set screw 629, and cannula 610 may be forced proximally through a lumen 631 within barrier 630 and out of engagement with the patient 13.

[00036] Additionally, cannula assembly 600 may completely lack attachment member 620. In such embodiments, cannula 610 directly engages barrier 630 (e.g., a threaded connection therebetween), and a distal-to-proximal disengagement of cannula 610 with respect to barrier 630 may not be feasible.

[00037] With particular reference to FIG. 5, barrier 630 is shown. Barrier 630 may be made from poly-ethylene, nylon, polypropylene, Acetal, ABS, poly-carbonate, Poly-sulphone,

PEEK, Radel, silicon, etc., and is configured to minimize or prevent contamination of mounting structure 500, instrument control unit 100, surgical instrument 10, etc. from bodily fluids that were in contact with cannula 610 during use, for example. Barrier 630 defines lumen 631, and includes a proximal ring 632, a proximal cylindrical section 634, a distal cylindrical section 636, and a distal ring 638. Proximal ring 632 is positioned adjacent to or in contact with a proximal face 540 of mounting structure 500. Proximal cylindrical section 634 extends distally from proximal ring 632 and is positioned within channel 530 of mounting structure 500 (e.g., within channel 530 of proximal housing 510). Distal cylindrical section 636 extends distally from proximal cylindrical section 634, extends through channel 530, and extends distally of a distal face 542 of mounting structure 500. Distal ring 638 is positioned adjacent to or in contact with distal face 542 of mounting structure 500, and radially surrounds a portion of distal cylindrical section 636. Distal ring 638 may be affixed to distal cylindrical section 636 or may be longitudinally movable with respect to distal cylindrical section 636. For example, distal ring 638 may be removable from the remainder of barrier 630. As shown in FIG. 5, at least one O-ring 639 may be included (e.g., integrated into barrier 630) to help ensure a secure engagement with little to no “play” between cannula 610 and barrier 630.

[00038] Further, a quick-connect mechanism may be utilized to enable or facilitate mechanical engagement between cannula 610, attachment member 620 and/or barrier 630. For example, attachment member 620 may include threads on proximal recess 624 which engage corresponding threads on distal cylindrical section 636 (e.g., the portion of distal cylindrical section 636 that extends distally of distal ring 638). A bayonet-, twist-, or snap-type connection may also be utilized between attachment member 620 and barrier 630.

[00039] With reference to FIG. 5, first seal 640 is disposed within proximal ring 632 of barrier 630. First seal 640, e.g., a septum seal or an instrument seal, is configured as a hole or opening, for instance, radially centered on proximal ring 632. First seal 640 is configured to maintain a fluid- and/or air-tight seal between areas located distally of first seal 640 and areas located proximally of first seal 640 while a surgical instrument (e.g., surgical instrument 10) extends through a hole 641 first seal 640 (e.g., to prevent or minimize the amount of insufflation gasses capable of escaping the patient during a surgical procedure). It is envisioned that first seal 640 is formed from the same material as barrier 630 (e.g., material directly adjacent hole 641 is made from the same material as barrier 630), or that first seal 640 includes a different material (e.g. disposable plastic or a reusable material) that is attached to barrier 630.

[00040] With continued reference to FIG. 5, second seal 650 is shown disposed within proximal housing 510 of mounting structure 500. Second seal 650, e.g., a duckbill seal, is radially centered within proximal cylindrical section 634 of barrier 630. Second seal 650 is configured to maintain a fluid- and/or air-tight seal between areas located distally of first seal 640 and areas located proximally of first seal 640 without the presence of a surgical instrument inserted therethrough (e.g., to prevent or minimize the amount of insufflation gasses capable of escaping the patient prior to a surgical instrument is inserted through cannula 610 and/or after a surgical instrument is removed from cannula 610). It is envisioned that second seal 650 is made from the same material as barrier 630 or from a different material.

[00041] The present disclosure also includes methods of engaging cannula 610 with mounting structure 500 of robot arm 3. For example, methods include inserting a portion of cannula 610 within mounting structure 500 in a distal-to-proximal direction. Methods also include removing the cannula 610 from engagement with mounting structure 500 in a proximal-

to-distal direction and/or a distal-to-proximal direction, inserting barrier 630 at least partially within channel 530 of mounting structure 500, engaging attachment member 620 with barrier 630, and removably securing attachment member 620 to cannula 610, for instance.

[00042] The use of cannula assembly 600 and mounting structure 500 may also enable nurses or assistants to insert the surgical instrument(s) 10 (as alignment is facilitated using mounting structure 500), while the surgeon focuses on the precise location of the end effector 20 of the surgical instrument 10 with respect to target tissue. This process may lead to faster instrument insertion, and may help prevent inadvertently contacting adjacent tissue with the end effector 20.

[00043] It will be understood that various modifications may be made to the embodiments disclosed herein. Therefore, the above description should not be construed as limiting, but merely as exemplifications of various embodiments. Those skilled in the art will envision other modifications within the scope and spirit of the claims appended thereto.

CLAIMS:

1. A surgical cannula assembly for use with a mounting structure of a robotic arm, the surgical cannula assembly comprising:

a cannula configured for reception of a surgical instrument at least partially therethrough;

an attachment mechanism configured to releasably engage the cannula; and

a barrier configured to extend through a channel of the mounting structure, the barrier including a proximal ring for positioning adjacent a proximal face of the mounting structure, a distal ring for positioning adjacent a distal face of the mounting structure, and a cylindrical section defining a lumen therein and extending between the proximal ring and the distal ring, the cannula configured for insertion within the lumen in a distal-to-proximal direction.

2. The surgical cannula assembly according to claim 1, wherein the barrier is configured to provide a sterile barrier between the cannula and the mounting structure during use.

3. The surgical cannula assembly according to claim 1, further comprising a first seal disposed within the lumen of the barrier and being configured to provide an air-tight seal about a surgical instrument that is inserted through a hole defined by the first seal.

4. The surgical cannula assembly according to claim 3, further comprising a second seal disposed within the lumen of the barrier and being configured to provide an air-tight seal within the lumen of the barrier in the absence of a surgical instrument within the lumen of the barrier.

5. The surgical cannula assembly according to claim 4, wherein the first seal and the second seal are made from the same material as the barrier.

6. The surgical cannula assembly according to claim 1, wherein the cannula is configured for removal from the lumen of the barrier in a proximal-to-distal direction.
7. The surgical cannula assembly according to claim 6, wherein the cannula is configured for removal from the lumen in a distal-to-proximal direction.
8. A method of engaging a cannula with a mounting structure of a robotic arm, comprising:

inserting a portion of a cannula within a channel of the mounting structure in a distal-to-proximal direction, the cannula providing a path through which a surgical instrument can be inserted in a proximal-to-distal direction at least partially therethrough to access a patient.
9. The method according to claim 8, further comprising removing the cannula from engagement with the mounting structure in a proximal-to-distal direction.
10. The method according to claim 8, further comprising inserting a barrier at least partially within the channel of the mounting structure.
11. The method according to claim 10, further comprising engaging an attachment member with the barrier, and removably securing the attachment member to the cannula.
12. The method according to claim 11, further comprising removing the cannula from engagement with the mounting structure in a distal-to-proximal direction.

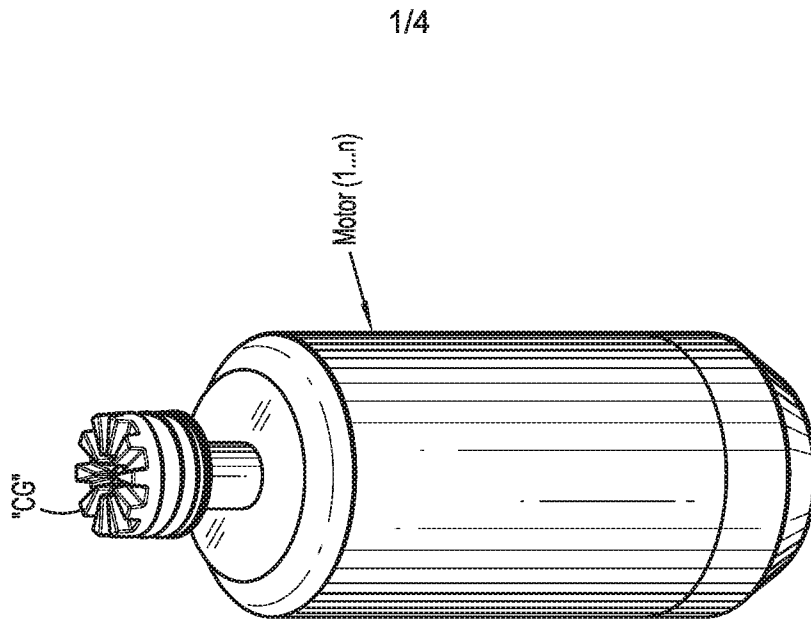


FIG. 1B

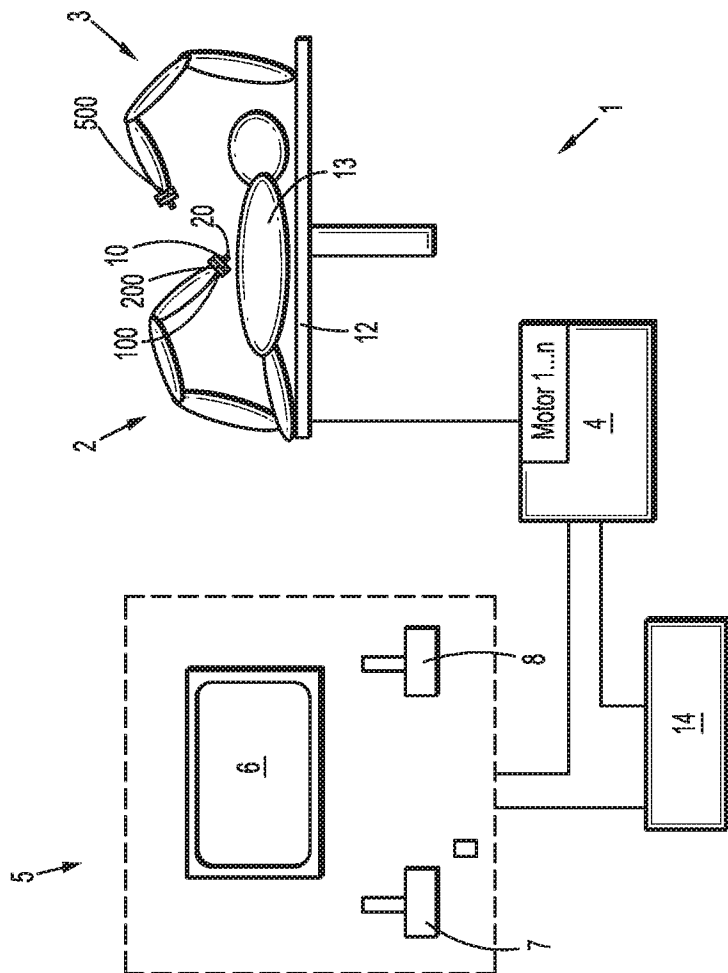
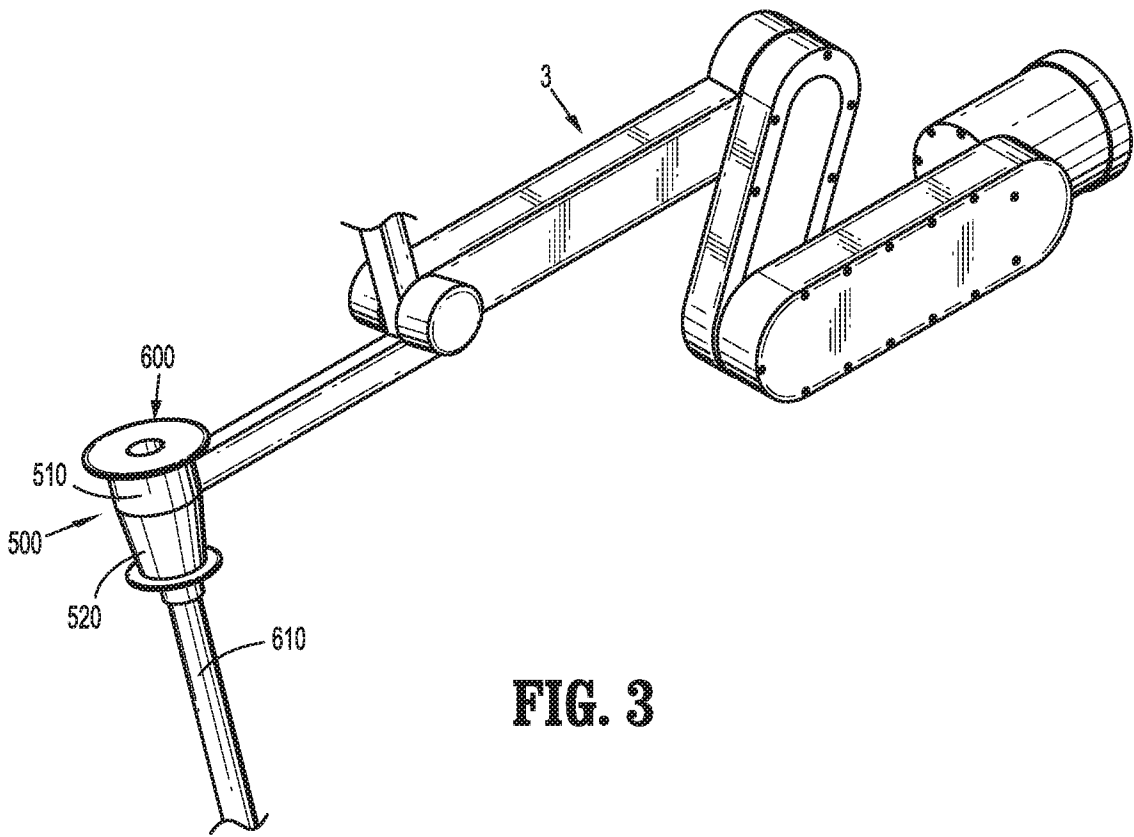
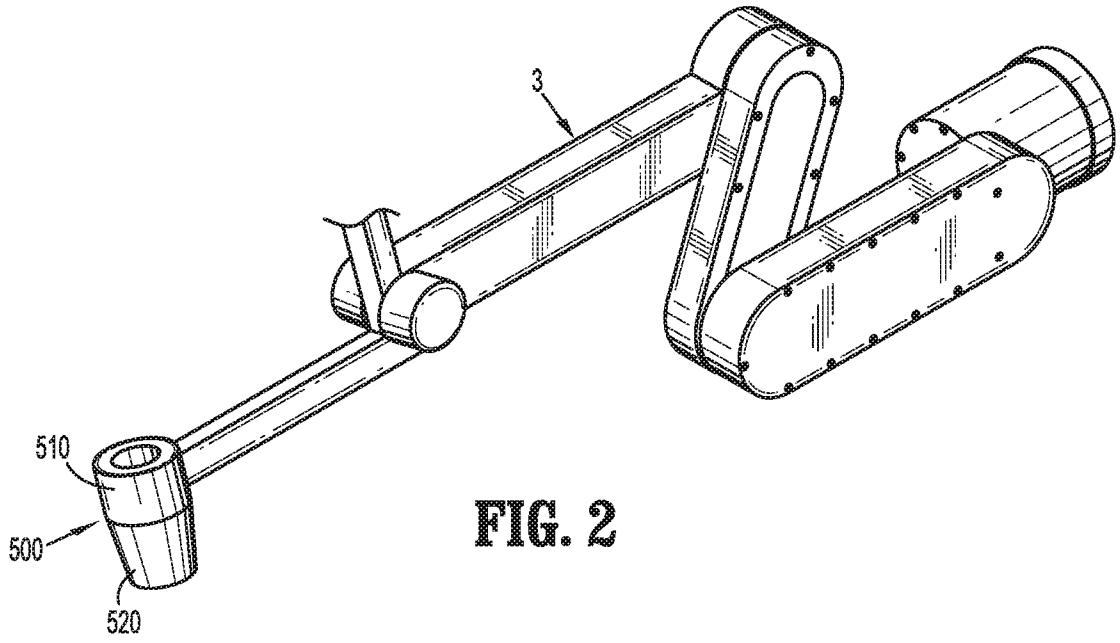


FIG. 1A



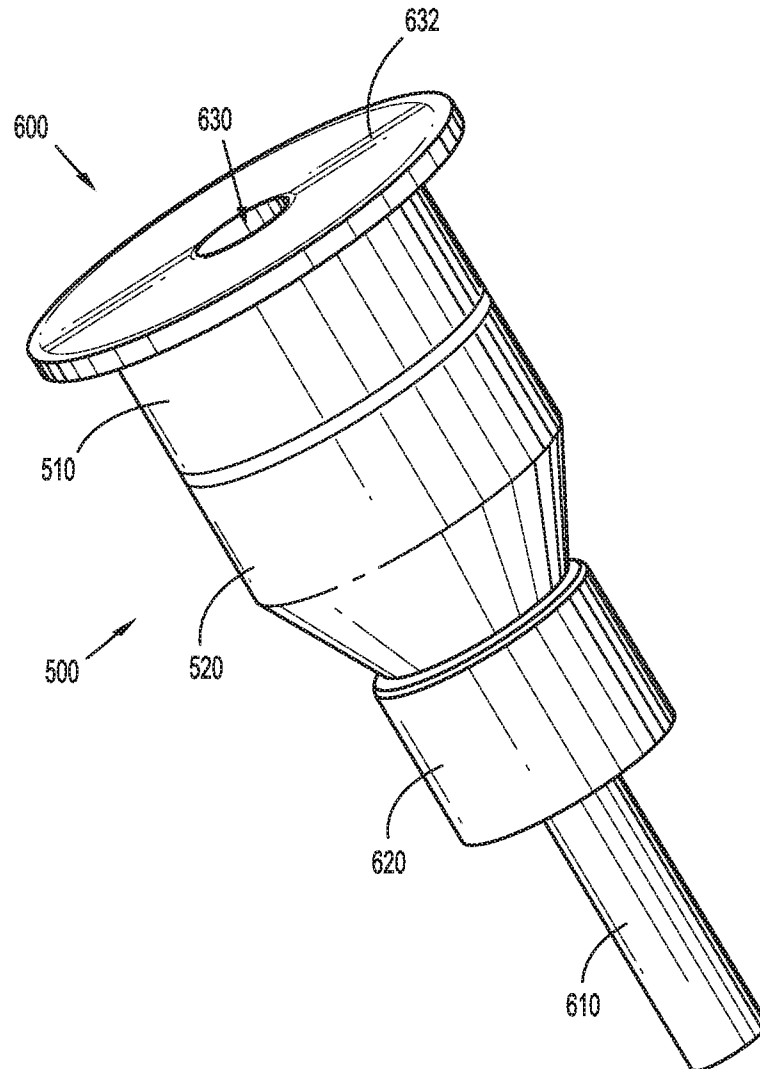


FIG. 4

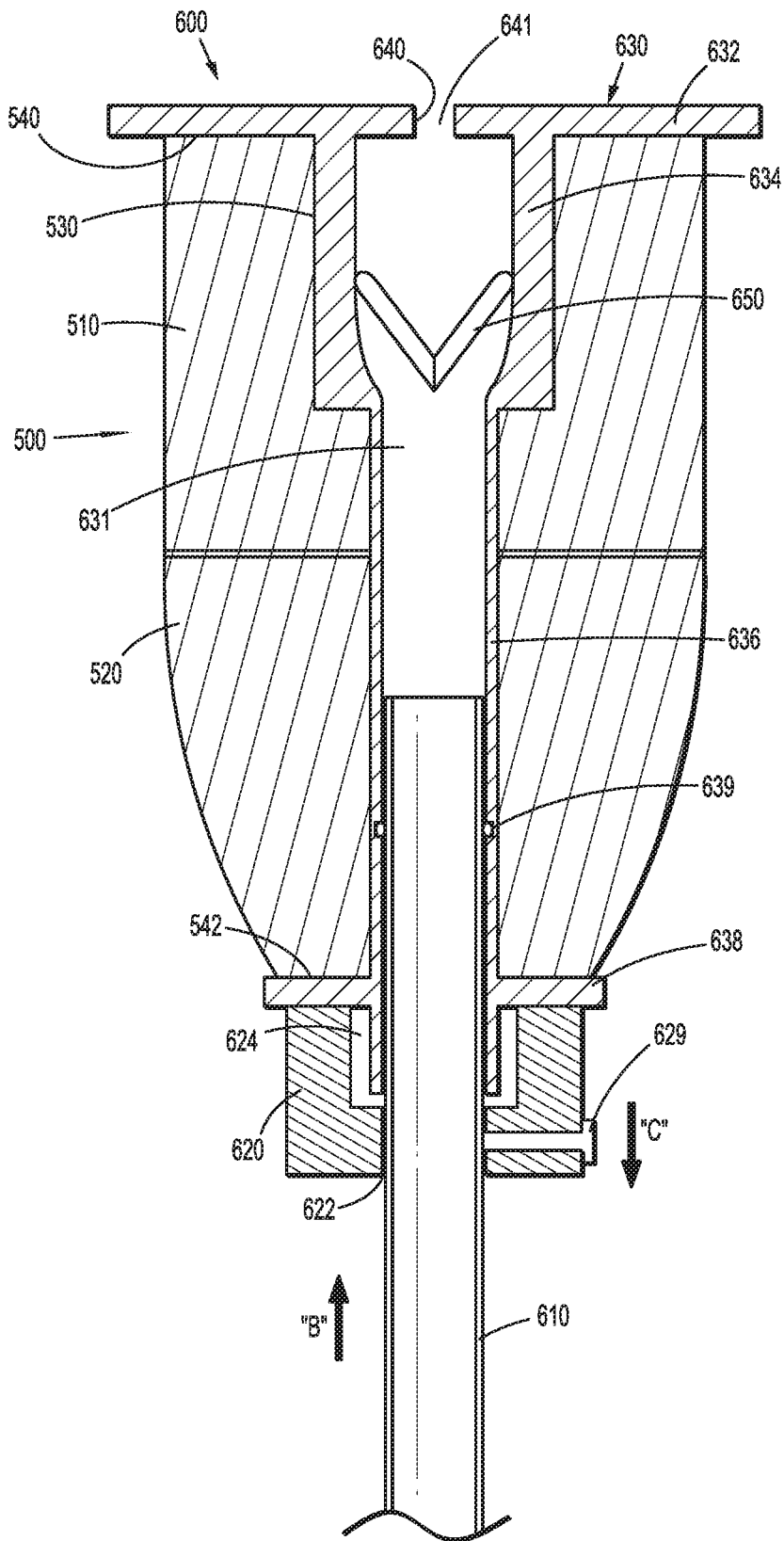


FIG. 5

A. CLASSIFICATION OF SUBJECT MATTER**A61B 34/30(2016.01)i, A61B 17/3209(2006.01)i, A61B 17/00(2006.01)i**

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHEDMinimum documentation searched (classification system followed by classification symbols)
A61B 34/30; A61B 17/34; A61M 5/00; A61B 19/00; A61B 17/00; F16C 11/10; A61B 17/3209Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched
Korean utility models and applications for utility models
Japanese utility models and applications for utility modelsElectronic data base consulted during the international search (name of data base and, where practicable, search terms used)
eKOMPASS(KIPO internal) & Keywords: surgical, arm, mounting, cannula, sterile, adaptor, connector, entry guide, clamp**C. DOCUMENTS CONSIDERED TO BE RELEVANT**

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
Y	US 2006-0161136 A1 (ANDERSON, C. S. et al.) 20 July 2006 See paragraphs [0071]-[0091]; figures 10-26B.	8,9
A		1-7,10-12
Y	US 2013-0164075 A1 (MURPHY, S. B.) 27 June 2013 See paragraphs [0015]-[0019]; figures 1-2.	8,9
A	US 2014-0296872 A1 (INTUITIVE SURGICAL OPERATIONS, INC.) 02 October 2014 See the whole document.	1-12
A	US 2013-0338679 A1 (TECHNISCHE UNIVERSITEIT EINDHOVEN) 19 December 2013 See the whole document.	1-12
A	EP 1625863 A2 (UNITED STATES SURGICAL CORPORATION) 15 February 2006 See the whole document.	1-12

 Further documents are listed in the continuation of Box C. See patent family annex.

* Special categories of cited documents:

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"T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention

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"Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art

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Date of the actual completion of the international search

12 September 2017 (12.09.2017)

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INTERNATIONAL SEARCH REPORT

Information on patent family members

International application No.

PCT/US2017/034178

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