



US008702748B2

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

(10) **Patent No.:** **US 8,702,748 B2**
(45) **Date of Patent:** **Apr. 22, 2014**

(54) **SMALL CALIBER LAPAROSCOPE
SURGICAL APPARATUS**

(75) Inventors: **Dong Jun Kim**, Goyang-si (KR); **Jun Woo Park**, Goyang-si (KR); **Yung Ho Jo**, Goyang-si (KR)

(73) Assignee: **National Cancer Center**, Gyeonggi-Do (KR)

(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 219 days.

(21) Appl. No.: **12/738,478**

(22) PCT Filed: **Oct. 16, 2008**

(86) PCT No.: **PCT/KR2008/006112**

§ 371 (c)(1),
(2), (4) Date: **Jul. 16, 2010**

(87) PCT Pub. No.: **WO2009/051418**

PCT Pub. Date: **Apr. 23, 2009**

(65) **Prior Publication Data**

US 2010/0280543 A1 Nov. 4, 2010

(30) **Foreign Application Priority Data**

Oct. 17, 2007 (KR) 10-2007-0104642

(51) **Int. Cl.**
A61B 17/00 (2006.01)

(52) **U.S. Cl.**
USPC **606/205**; 606/206; 606/207

(58) **Field of Classification Search**
CPC A61B 2019/2942
See application file for complete search history.

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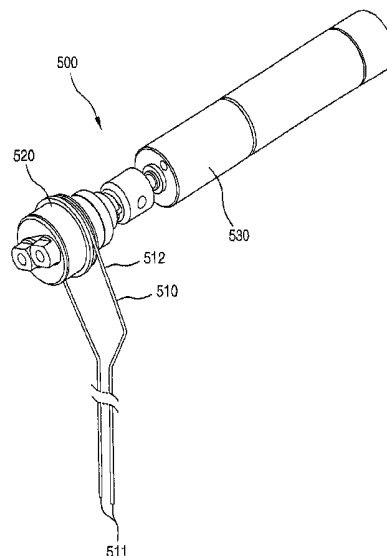
Assistant Examiner — Kendra Obu

(74) *Attorney, Agent, or Firm* — Seed IP Law Group PLLC

(57) **ABSTRACT**

A laparoscopic surgical instrument includes a shaft and a head having a distal end to which a variety of surgical instruments are attached. The laparoscopic surgical instrument also includes a flexible joint installed between the shaft and the head; a longitudinal-driving unit including a longitudinal-driving wire connected with both longitudinal ends of the head and a longitudinal-driving roller turning the longitudinal-driving wire and a transverse-driving unit including a transverse-driving wire connected with both transverse ends of the head and a transverse-driving roller turning the transverse-driving wire. The longitudinal-driving unit turns the flexible joint in the longitudinal direction, the transverse-driving unit turns the flexible joint in the transverse direction, and the shaft has a small diameter.

10 Claims, 13 Drawing Sheets



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Fig. 1

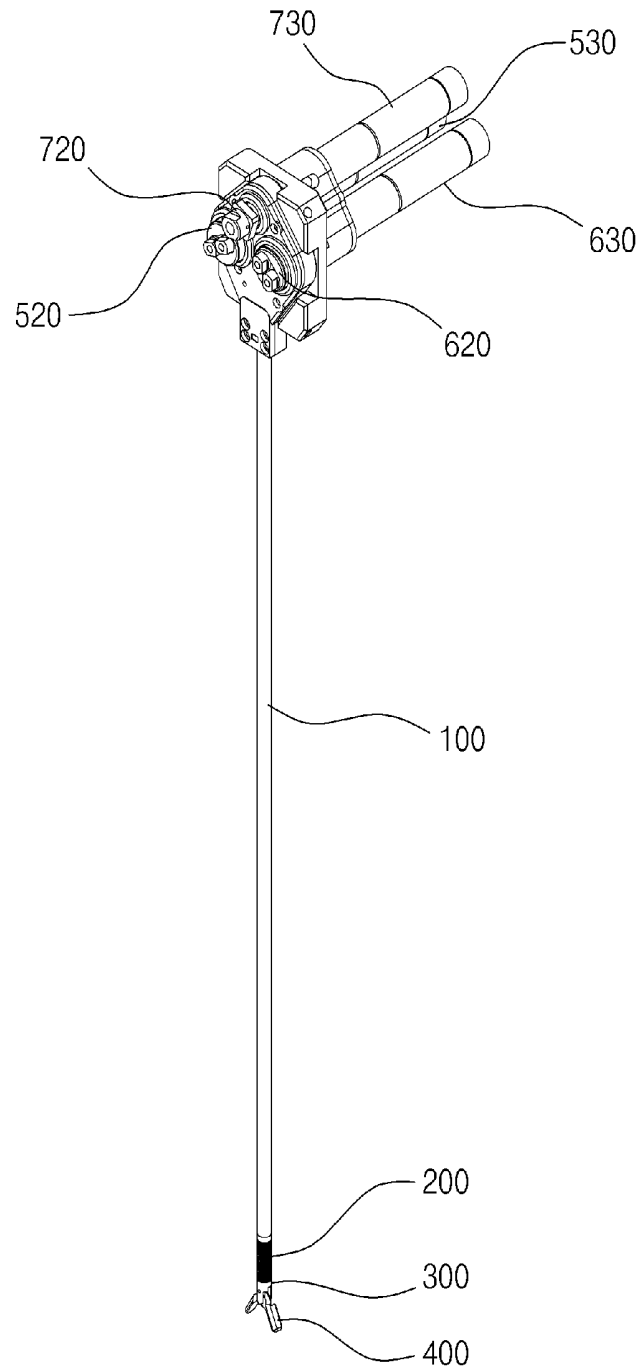


Fig. 2

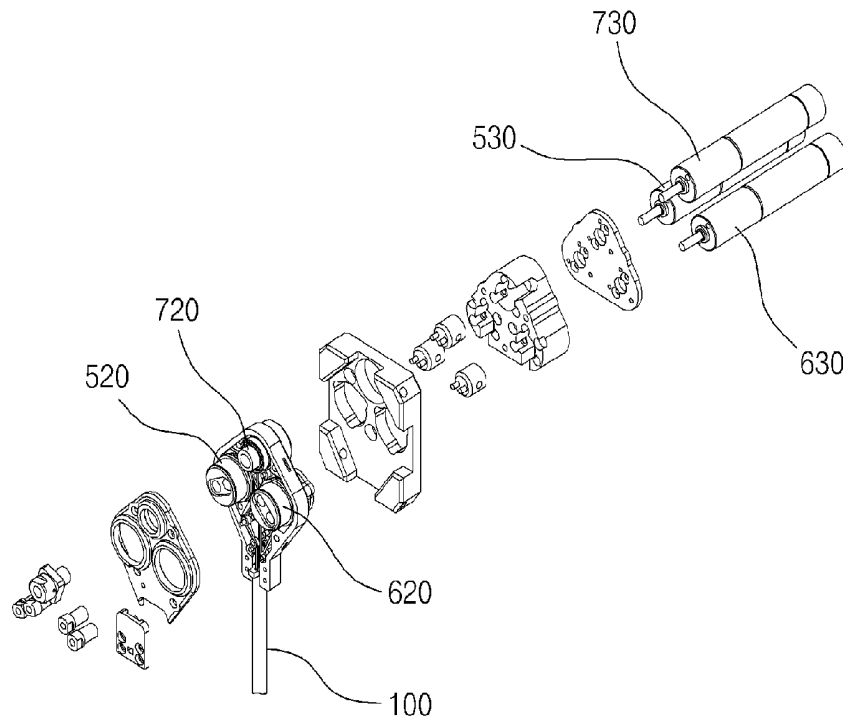


Fig. 3

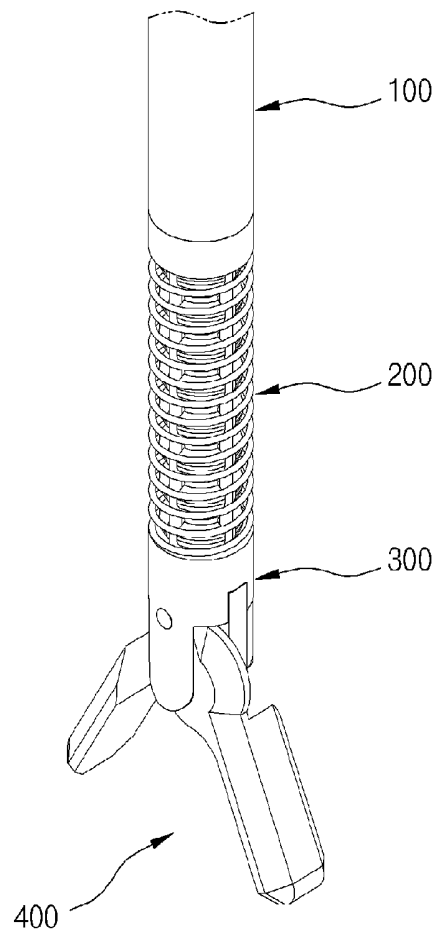


Fig. 4

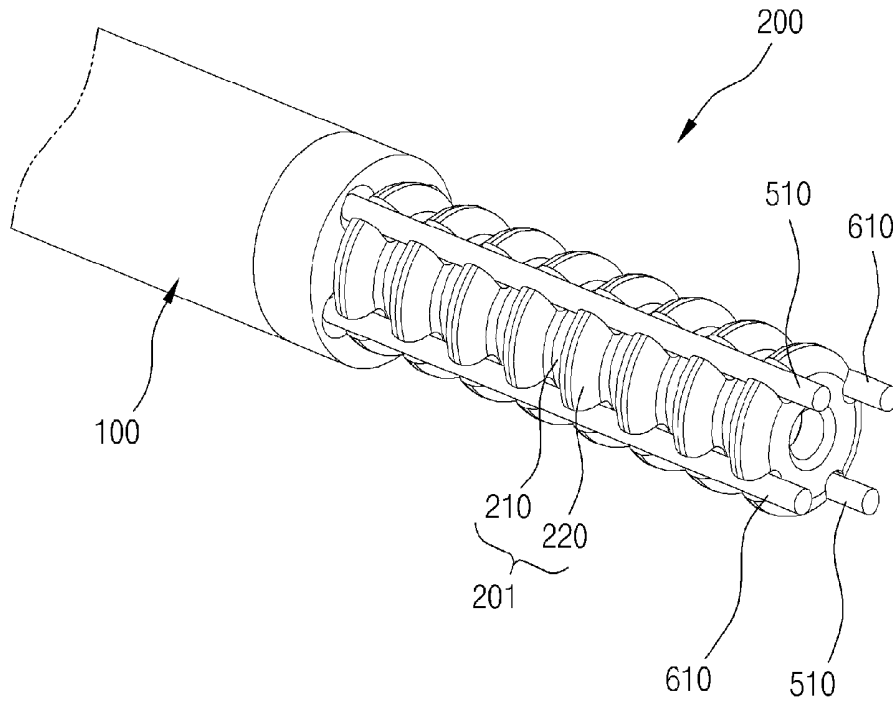


Fig. 5

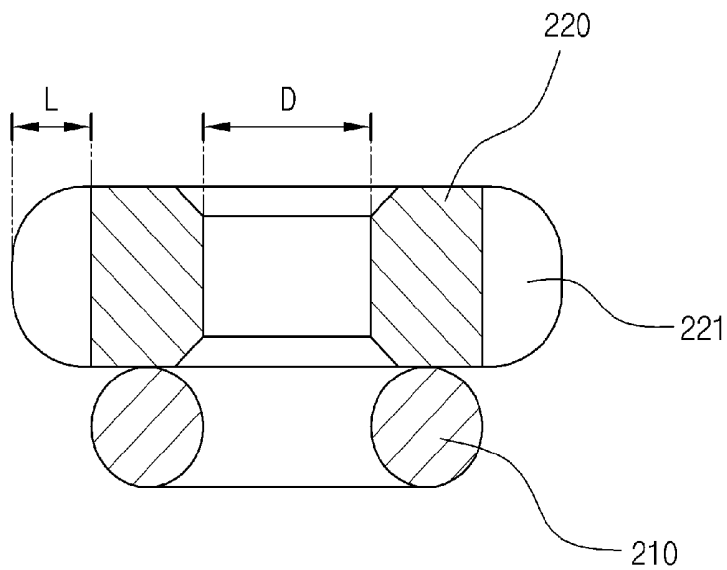


Fig. 6

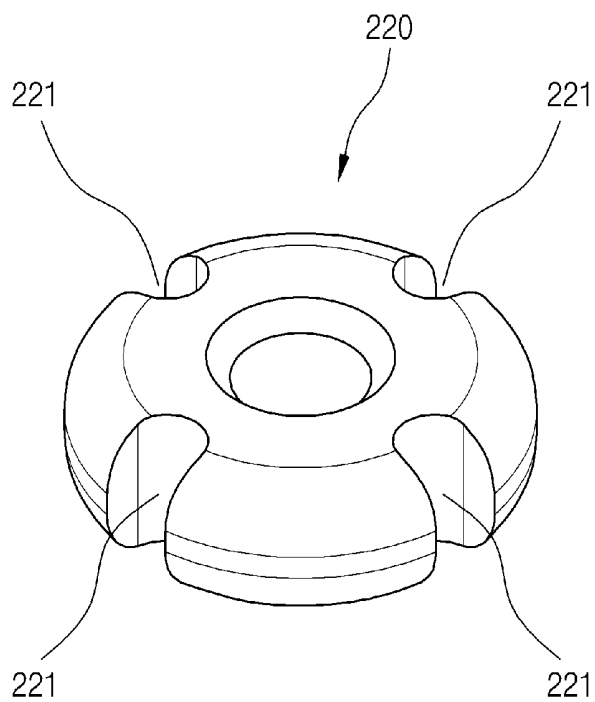


Fig. 7

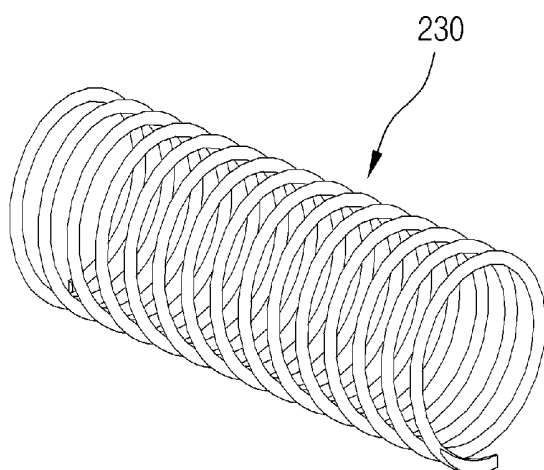


Fig. 8

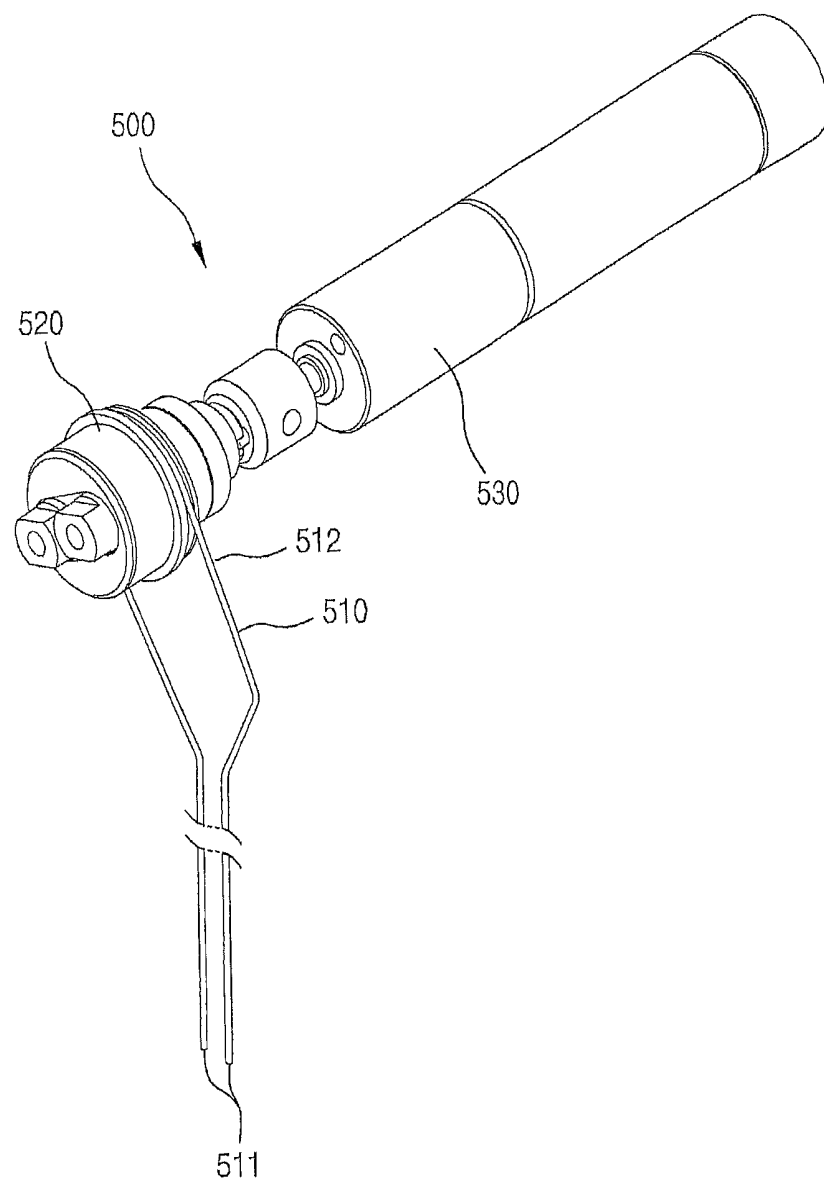


Fig. 9

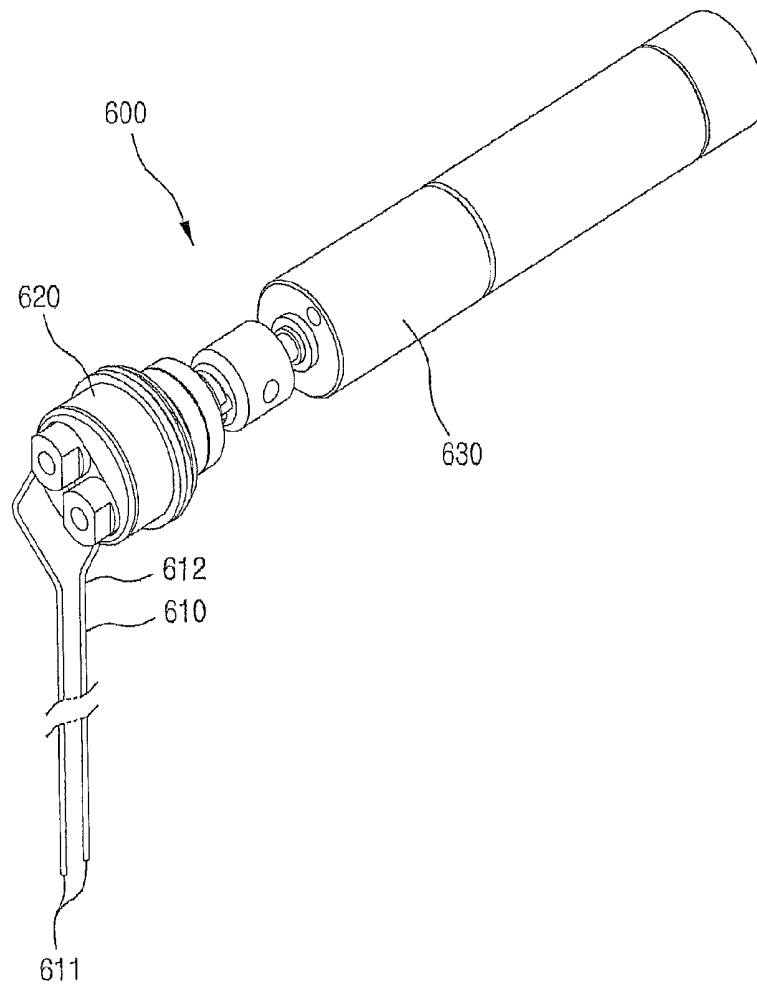


Fig. 10

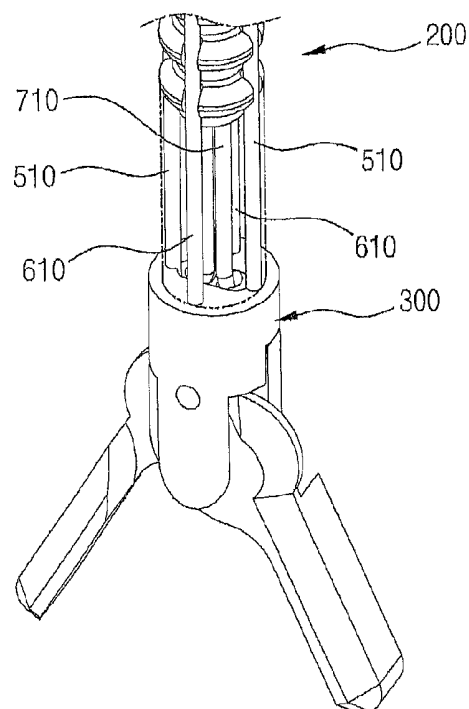


Fig. 11

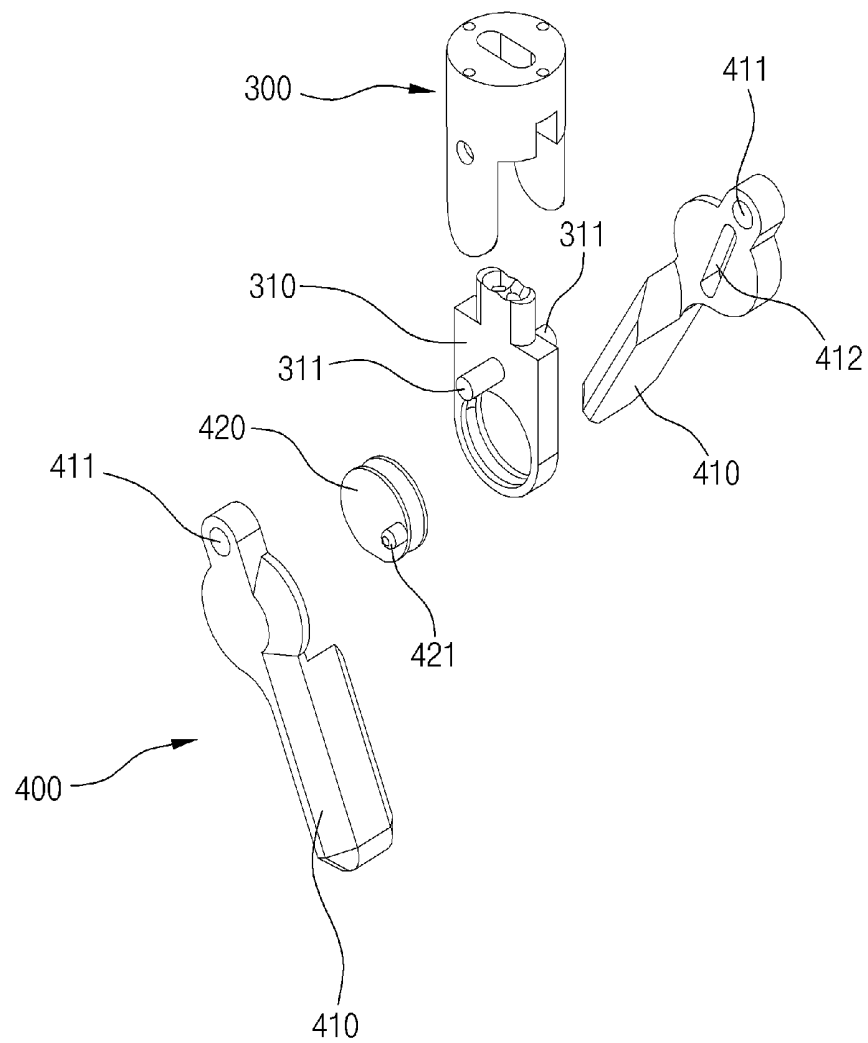


Fig. 12

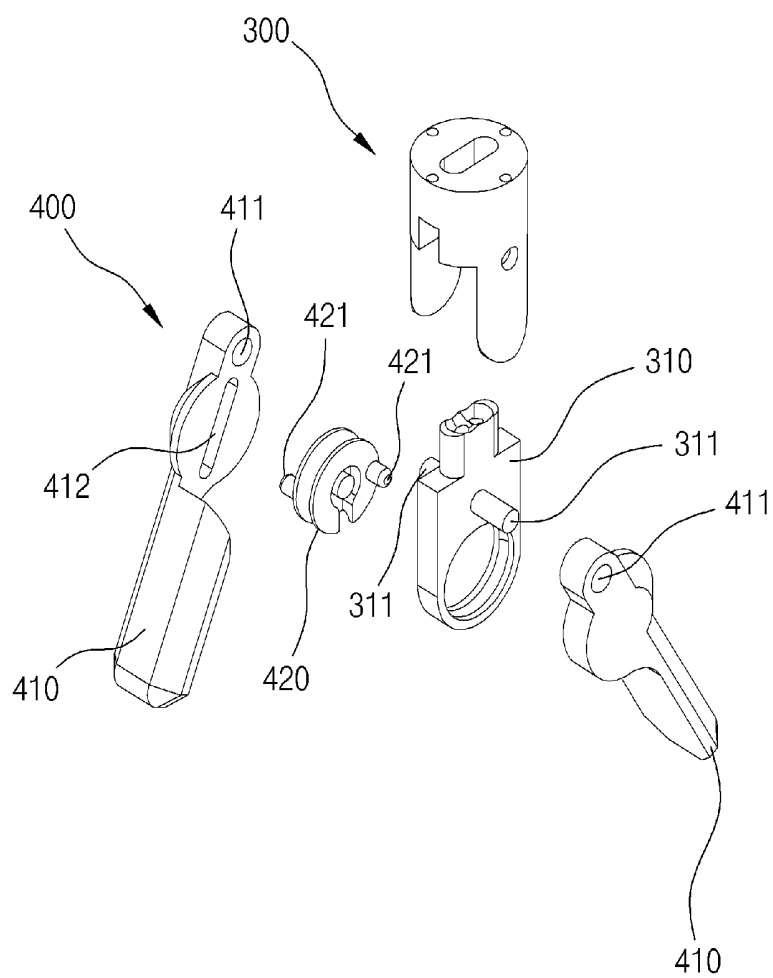


Fig. 13

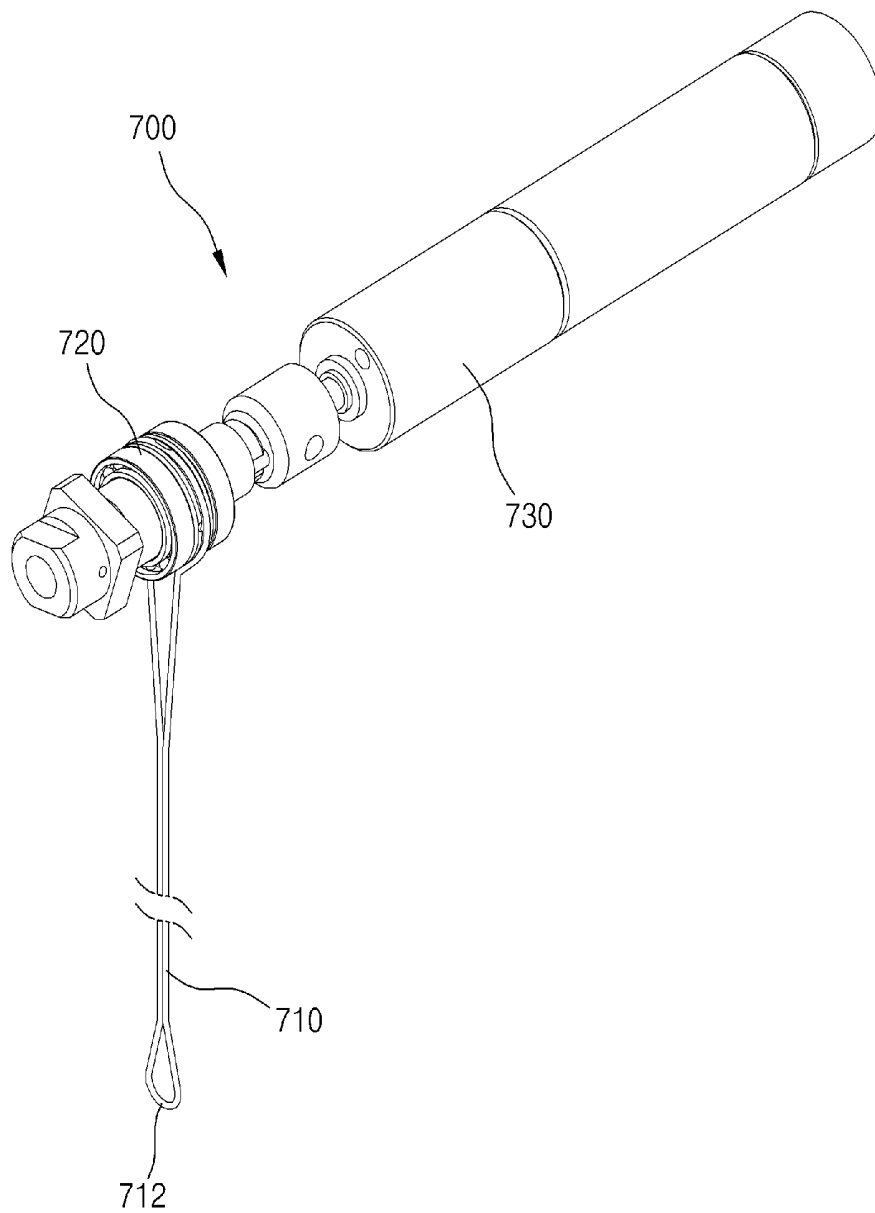


Fig. 14

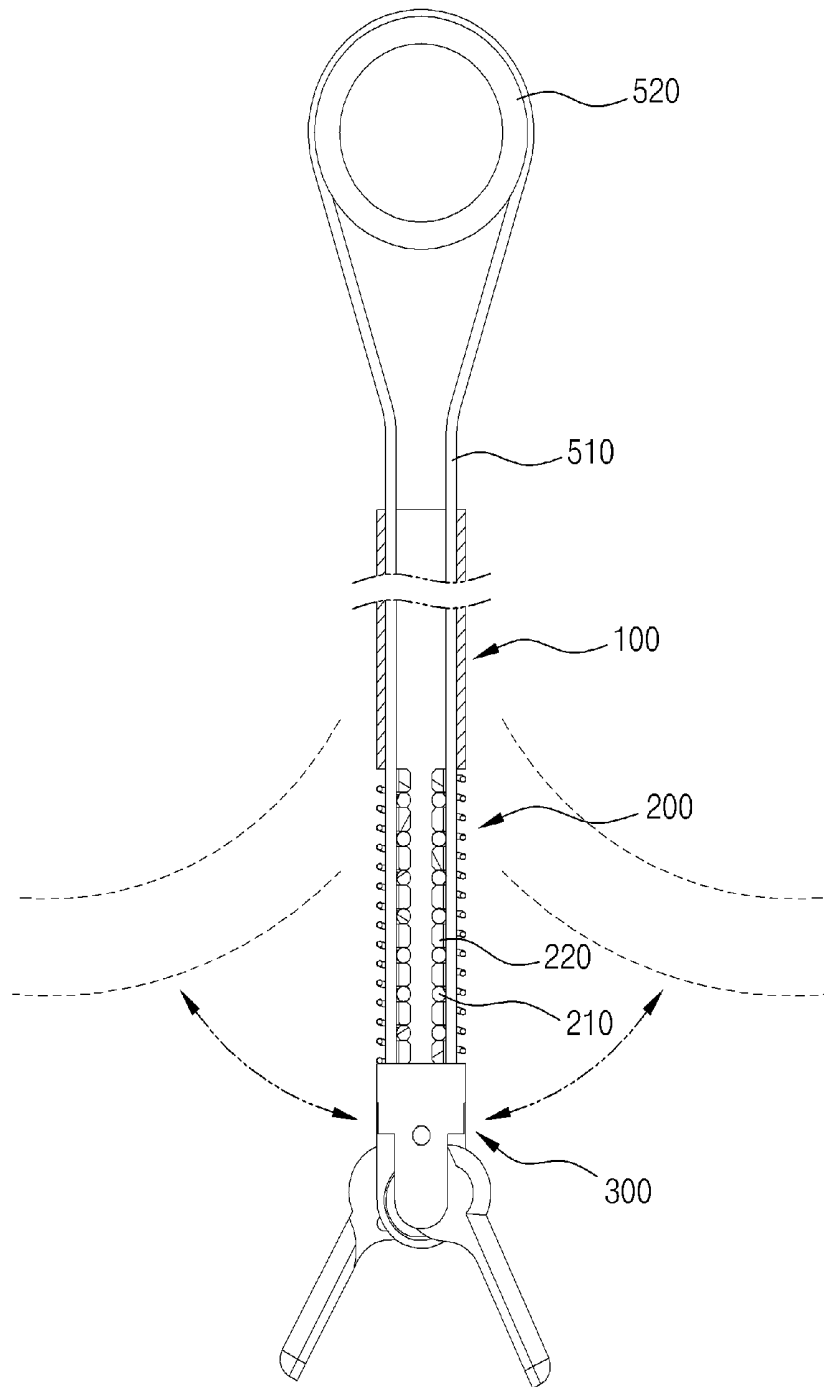


Fig. 15

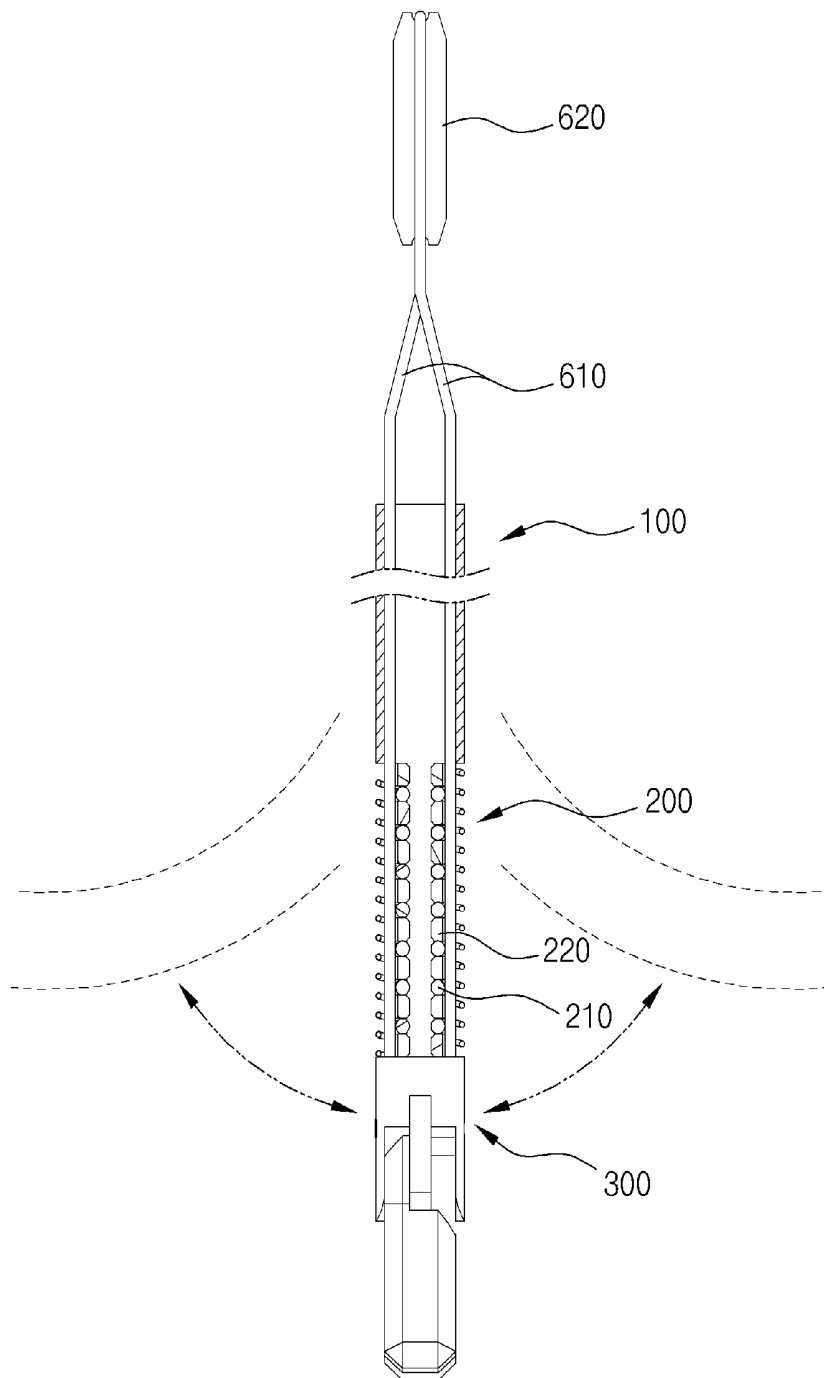


Fig. 16

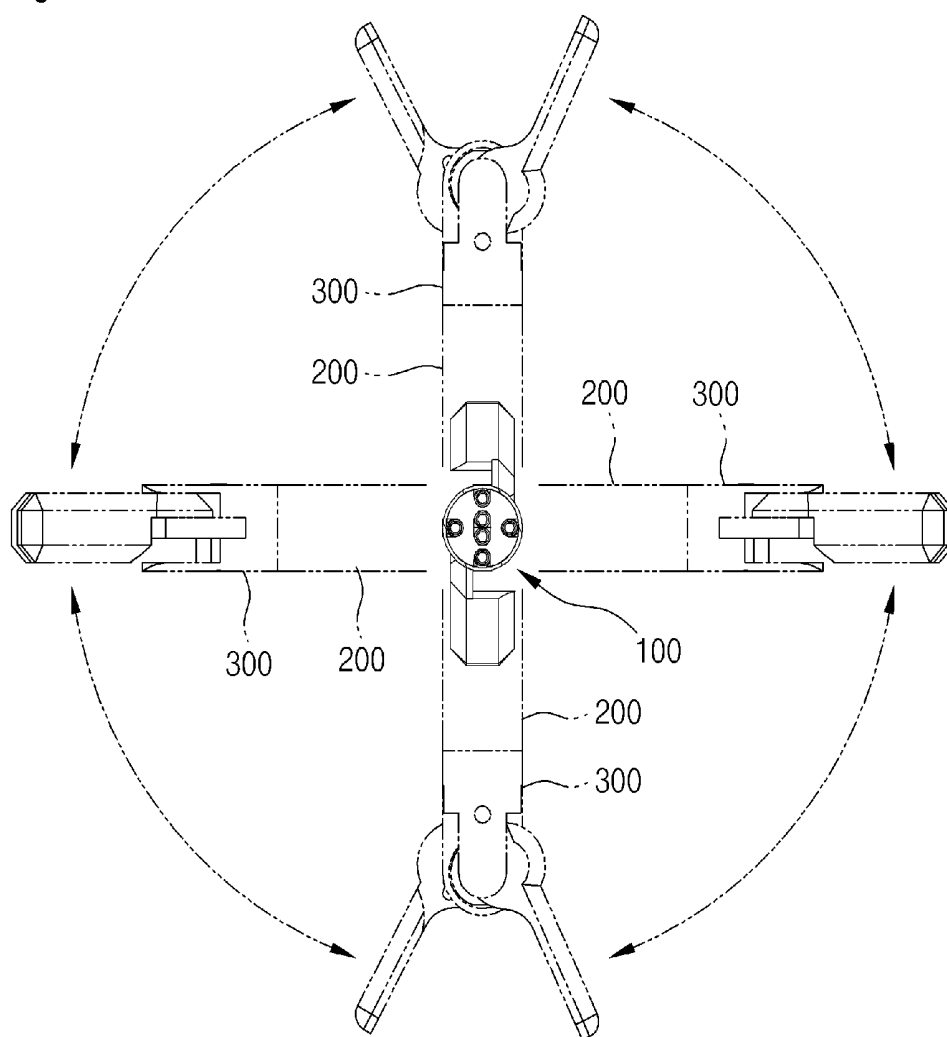
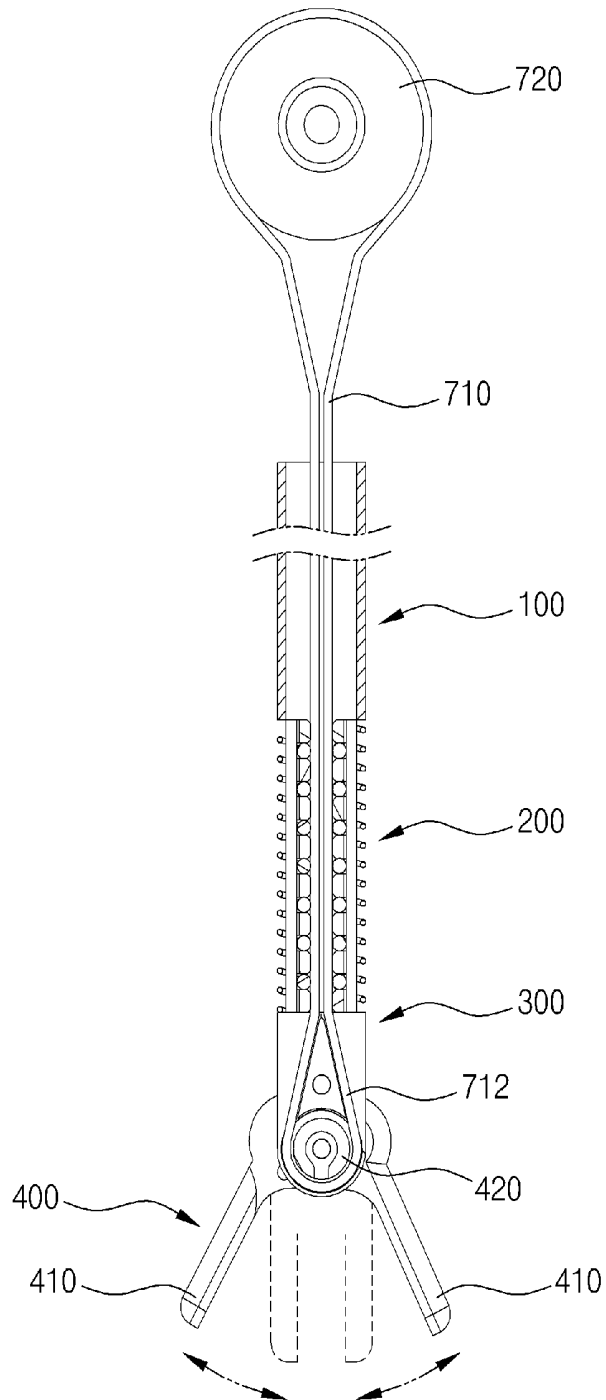


Fig. 17



SMALL CALIBER LAPAROSCOPE SURGICAL APPARATUS

This application is the U.S. National Stage of International Application No. PCT/KR2008/006112, filed 16 Oct. 2008, which designates the U.S., published in English, and claims priority under 35 U.S.C. §§119 or 365(c) to Korean Application No. 10-2007-0104642, filed 17 Oct. 2007. The entire teachings of the above applications are incorporated herein by reference.

TECHNICAL FIELD

The present invention relates to a laparoscopic surgical instrument used for laparoscopic surgery, and more particularly, to a laparoscopic surgical instrument having a small diameter shaft, wherein a flexible joint is installed between a shaft and a head of the laparoscopic surgical instrument, thereby freely rotating the head.

BACKGROUND ART

Laparoscopic surgery is a surgical procedure in which a small incision of approximately one centimeter is made around the navel, through which an endoscope (laparoscope) and several surgical instruments are inserted to perform surgical procedures. In contrast to open abdominal surgery, laparoscopic surgery usually involves less pain, less scarring, and reduced recovery time after the operation since laparoscopic surgery only needs one or more small incisions to be made in the abdomen. Because of these advantages, the use of laparoscopic surgery as a popular diagnostic and treatment tool for a variety of diseases has increased.

Laparoscopic surgery can be directly performed with surgical instruments or be done with small robotic arms by surgeons. An example of a robot-assisted laparoscopic surgery is disclosed in Korean Patent No. 10-0585458, and the surgeon guides the movement of slave robotic arms and surgical instruments by manipulating a master robot.

During a robot-assisted laparoscopic surgery, the surgeon can perform the surgery at a console several feet away from a patient. Further, the robot-assisted laparoscopic surgery can be done in the same way the experienced surgeon does, even though the surgeon is not at the operating table.

Since the surgeons experience less physical and mental fatigue during laparoscopic surgery compared to open abdominal surgery during a surgical operation, they can as a result take care of more patients.

In laparoscopic surgery, the endoscope (laparoscope) and more than two surgical instruments are basically used. The endoscope is used to provide images of the internal organs for the surgeon to see. As the surgical instruments are special tools and devices provided for a surgical operation, grasping forceps are normally attached to the head of the instrument and are used to block blood vessels and to suture tissues.

The surgical instruments need to be made in a minimal size in order to minimize invasive damage to the body of the patient. For an accurate surgical operation of internal organs, a joint can be formed between a shaft and a head portion of the surgical instrument so that the head portion can rotate within a certain angle. An example of the surgical instrument formed with the joint is disclosed in Korean Patent No. 10-2006-0056238. In this prior art, the joint actuated by a gear is installed between the head and shaft.

In the surgical instrument having a joint actuated by a gear between the shaft and the head, there is a limit in making the diameters of the shaft and the head smaller attributable to the

size of the gear. Further, there have been problems with the development and the production of the instrument because of the complicated driving means to manipulate and actuate the gear in the joint.

In laparoscopic surgery with the surgical instrument having the joint between the shaft and the head, the surgical operation can be done with minimized incisions in the abdomen. However, as the sizes of the shaft and the head become bigger due to the size of the joint, the incision needs to become bigger such that the shaft can be inserted into the patient's abdomen.

Besides, the joint actuated by the gear can rotate the head by certain degrees at regular intervals depending on the gear ratio, and thus the head cannot rotate as much as the clinician wants.

Further, only one joint actuated by the gear is not enough to rotate the head in all directions and more than two joints are needed to resolve this problem. In this case, in order to move the joints, the devices become complicated and the diameter of the shaft needs to be bigger, as a result raising the cost of manufacturing the surgical instruments.

DISCLOSURE OF INVENTION

Technical Problem

The present invention has been proposed to solve the aforementioned problems and embodiments of the present invention provide a joint rotating in multiple degrees of freedom between a shaft and a head of a laparoscopic surgical instrument in order to improve the rotating range of the head.

Embodiments of the present invention also provide a laparoscopic surgical instrument having a small diameter shaft in order to minimize the incision on the body of the patient made during surgical operations.

Technical Solution

In an exemplary embodiment of the present invention, the laparoscopic surgical instrument includes a shaft and a head having a distal end to which a variety of surgical instruments are attached. The laparoscopic surgical instrument may include a flexible joint installed between the shaft and the head; a longitudinal-driving unit including a longitudinal-driving wire connected with both longitudinal ends of the head and a longitudinal-driving roller turning the longitudinal-driving wire, wherein the longitudinal-driving unit turns the flexible joint in the longitudinal direction; and a transverse-driving unit including a transverse-driving wire connected with both transverse ends of the head and a transverse-driving roller turning the transverse-driving wire, wherein the transverse-driving unit turns the flexible joint in the transverse direction, wherein the shaft has a small diameter.

The longitudinal-driving wire of the longitudinal-driving unit is partially wound on the longitudinal-driving roller, the transverse-driving wire of the transverse-driving unit is partially wound on the transverse-driving roller, and both ends of the longitudinal-driving wire and the transverse-driving wire are inserted into the shaft and extend through outside of the flexible joint so as to be connected with the head.

The flexible joint includes a plurality of rings arranged in a row.

The plurality of rings includes small rings and large rings arranged in a row to repeatedly cross each other.

The small rings and the large rings are made of elastic material.

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Each of the large rings has guide grooves on outer portions thereof such that the longitudinal-driving wire and the transverse-driving wire are linearly inserted into the guide grooves.

The guide grooves are arranged in the exterior circumferential portions of the large ring at 90 degree intervals.

The laparoscopic surgical instrument may further include an outer cover attached to an outside of the flexible joint so as to prevent the longitudinal-driving wire and the transverse-driving wire from moving out of the guide grooves of the large rings.

The laparoscopic surgical instrument may further include a steel wire that is repeatedly wound into a coil shape with an equal diameter.

The laparoscopic surgical instrument may further include forceps included or connected to the head. The forceps include a 2 forcep jaws separated to top and bottom sides and rotatably attached to the head; a driving roller rotating the forceps; and a forceps-driving unit actuating the driving roller to turn the forceps.

Each of the forcep jaws has a guide slit formed inside thereof. The driving roller is rotatably coupled with the body connected with the head and has driving pins formed on both sides, each of the driving pins connected with the guide slit of each of the forcep jaws.

The forceps-driving unit includes a forceps-driving wire inserted through the shaft, the flexible joint and a through-hole of the head, and having a folded portion wound on an exterior circumference of the driving roller; a forceps-driving roller provided on an upper portion of the shaft such that a terminal portion of the forceps-driving wire is wound thereon; and a forceps-driving motor turning the forceps-driving roller.

Advantageous Effects

In the exemplary embodiment of the present invention, the laparoscopic surgical instrument is provided with the flexible joint between the shaft and the head, a flexible joint which can be made smaller and simpler with lower production cost compared to the gear-type joint in the prior art, and a shaft and a head which can be made in a small diameter.

The flexible joint of the laparoscopic surgical instrument having a small diameter shaft in accordance with the present invention can be more precisely controlled compared to the gear-type joint actuated by the gear in the prior art.

In addition, since the laparoscopic surgical instrument of the present invention is equipped with the shaft and the head having small diameters, invasive damage to the body of the patient can be minimized, thereby reducing post-surgery recovery time.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 is a perspective view illustrating a laparoscopic surgical instrument having a small diameter shaft in accordance with an embodiment of the present invention;

FIG. 2 is an exploded perspective view illustrating the driving unit of the laparoscopic surgical instrument of FIG. 1;

FIG. 3 is an exploded perspective view illustrating the flexible joint, the head and the forceps of the laparoscopic surgical instrument of FIG. 1;

FIG. 4 is an enlarged perspective view of the flexible joint of FIG. 1;

FIG. 5 is a cross-sectional view illustrating the small ring and the large ring of the flexible joint of FIG. 4 in detail;

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FIG. 6 is an enlarged perspective view of the large ring of FIG. 5;

FIG. 7 is an enlarged perspective view of the outer cover of the flexible joint of FIG. 4;

FIG. 8 is an enlarged perspective view of the longitudinal-driving unit of the laparoscopic surgical instrument having a small diameter shaft in accordance with an embodiment of the present invention;

FIG. 9 is an enlarged perspective view of the transverse-driving unit of the laparoscopic surgical instrument having a small diameter shaft;

FIG. 10 is an enlarged perspective view illustrating the assembled state of the head of FIG. 3 with the flexible joint, the longitudinal-driving wire, and the transverse-driving wire;

FIGS. 11 and 12 are exploded perspective views illustrating the forceps of FIG. 10;

FIG. 13 is a perspective view showing the details of a forceps-driving unit of a laparoscopic surgical instrument having a small diameter shaft in accordance with an embodiment of the present invention;

FIG. 14 is a perspective view showing the operating status of the laparoscopic surgical instrument having a small diameter shaft in accordance with an embodiment of the present invention, in which the head is longitudinally driven by the longitudinal-driving unit;

FIG. 15 is a perspective view showing the operating status of the laparoscopic surgical instrument having a small diameter shaft in accordance with an embodiment of the present invention, in which the head is transversely driven by the transverse-driving unit;

FIG. 16 is a top plan view showing the rotating state of the head around the shaft in the laparoscopic surgical instrument having a small diameter shaft in accordance with an embodiment of the present invention; and

FIG. 17 is a perspective view showing the operating state of the forceps in the laparoscopic surgical instrument having a small diameter shaft in accordance with an embodiment of the present invention.

BEST MODE FOR CARRYING OUT THE INVENTION

The features and other advantages of the present invention will be more clearly understood from the following detailed description taken in conjunction with the accompanying drawings. Hereinafter, a laparoscopic surgical instrument having a small diameter shaft will be described more in detail with reference to the accompanying drawings in accordance with the preferred embodiments of the present invention.

Referring to FIGS. 1 to 3, the laparoscopic surgical instrument having a small diameter shaft includes an elongated shaft 100 inserted into an incision in the abdomen; a flexible joint 200 connected with the distal portion of the shaft 100; a head 300 connected with the bottom portion of the flexible joint 200; forceps 400 (a surgical instrument) installed at the bottom portion of the head 300; and drive portions 500, 600 and 700 each of which actuates a respective one of the flexible joint 200 and the forceps 400.

The shaft 100 is inserted into the operation region during the surgical operation, formed as an elongated shape with a hollow tube inside, and both ends of the shaft 100 are opened.

Referring to FIGS. 4 to 6, the flexible joint 200 is structured with a plurality of rings 201 arranged in a row. Each of the rings 201 consists of a small ring 210 and a large ring 220. Both the small and large rings 210 and 220 have the same internal diameter "D." The reason is that a strait hollow with

a uniform diameter can be formed inside the flexible joint **200** such that the wires or power lines can pass through the straight hollow. Each of the large rings **220** is provided with guide grooves **221** for inserting a longitudinal-driving wire **510** and a transverse-driving wire **610** which will be described below in four portions of the exterior circumference thereof. The guide grooves **221** are formed in the exterior circumference of the large ring at 90 degrees intervals. The large rings **220** can be preferably manufactured larger than the small rings **210** by the depth "L" of the guide grooves **221**.

The rings **201** of the flexible joint **200** can be made of hard material such as steel or soft material with elasticity such as rubber.

The flexible joint **200** configured as aforementioned is connected at the top portion thereof with the shaft **100** and at the bottom portion thereof with the head **300**, respectively.

Referring to FIGS. **4** and **7**, the flexible joint **200** is covered with a coil-shaped outer cover **230**, which is formed by repeatedly winding a steel wire in the same diameter. The outer cover **230** prevents the longitudinal-driving wire **510** and the transverse-driving wire **610** from moving out of the guide grooves **221** of the large rings **220** when the flexible joint **200** is bending.

The outer cover **230** is illustrated and described as a coil-shaped figure as above. However, the present invention is not restricted to the above-described figure, and the outer cover **230** can be made of a hose which cannot expand and contract in a circle direction while expanding and contracting in the longitudinal direction. For this hose, an accordion-shaped hose or a flexible style pipe can be used.

Referring to FIGS. **8** and **14**, the longitudinal-driving unit **500** actuates the flexible joint **200** to fold in the longitudinal direction of the head **300**, and includes the longitudinal-driving wire **510**, a longitudinal-driving roller **520**, and a longitudinal-driving motor **530**.

The longitudinal-driving wire **510** is implemented with one wire. The longitudinal-driving wire **510** is bent in such a fashion that opposite terminal portions **511** join in one direction, and then the distal ends thereof where the terminal portions **511** are located are inserted into the distal end of the shaft **100**. The longitudinal-driving wire **510** inserted into the shaft **100** is linearly inserted into two longitudinally-directed groove sets of the guide grooves **221** (see FIG. **6**) of the large rings **220** in the flexible joint **200**, and both terminal portions **511** are connected with both longitudinally-directed connecting ends of the head **300**. A joining portion **512** of the longitudinally-drive wire **510** is located on the top portion (proximal portion) of the shaft **100** and is wound on the longitudinal-driving roller **520** connected with the longitudinal-driving motor **530**. Preferably, the longitudinal-driving wire **510** can be wound so as to be rotatable in both directions of the longitudinal-driving roller **520**.

The longitudinal-driving wire **510** wound on the longitudinal-driving roller **520** moves in the direction where the longitudinal-driving roller **520** rotates. When the longitudinal-driving roller **520** rotates in the right direction, the right side terminal portion **511** of the longitudinal-driving wire **510** comes out and the opposing left side terminal portion **511** is inserted therein.

Referring to FIGS. **9** and **15**, the transverse-driving unit **600** actuates the flexible joint **200** to fold in the transverse direction of the head **300**, and includes the transverse-driving wire **610**, the transverse-driving roller **620**, and the transverse-driving motor **630**.

Referring to the transverse-driving unit **600** configured as above, the transverse-driving wire **610** is implemented with

one wire like the longitudinal-driving wire **510** (see FIG. **8**). The transverse-driving wire **610** is bent in such a fashion that opposite terminal portions **611** join in one direction, and then the distal ends thereof where the terminal portions **611** are located are inserted into the distal end of the shaft **100**. The transverse-driving wire **610** inserted into the shaft **100** is inserted linearly into the two transversely-directed guide grooves (refer to **221** of FIG. **6**) among the guide grooves **221** of the large rings **220** in the flexible joint **200**, and both the terminal portions **611** are connected with both transversely-directed connecting ends of the head **300**. The joint portion **612** of the transverse-driving wire **610** is located on the top portion (proximal portion) of the shaft **100** and is wound on the transverse-driving roller **620** connected with the transverse-driving motor **630**.

The transverse-driving wire **610** wound on the transverse-driving roller **620** is moving in the direction where the transverse-driving roller **620** rotates. When the transverse-driving roller **620** rotates in the right direction based on the shaft **100**, the right side terminal portion **611** of the transverse-driving wire **610** comes out and the opposing left side terminal portion **611** is inserted therein.

Referring to FIG. **10**, the head **300** has the same external diameter as the shaft (refer to **100** of FIG. **1**) and is attached to the distal bottom end of the flexible joint **200**. Both the terminal portions **511** of the longitudinal-driving wire **510** and both the terminal portions **611** of the transverse-driving wire **610** are attached to both sides of the connecting surfaces in the longitudinal direction and on both sides of the connecting surfaces in the transverse direction, respectively. On the distal bottom end of the head **300**, a variety of surgical instruments are attached or constructed as one body.

Referring to FIGS. **11** to **13**, the forceps **400** include a pair of forcep jaws **410** attached to the body **310**, which is connected with the head **300**, a driving roller **420**, and a forceps-driving unit **700**.

The forceps jaw **410** is formed with a piercing pivot insertion opening **411** on the top portion thereof and a guide slit **412** elongated along an inclination inside the jaw **410**. The driving roller **420** is rotatably installed on the body **310** and formed with driving pins **421** eccentrically protruded on both sides. The forceps-driving unit **700** includes a forceps-driving wire **710**, a forceps-driving roller **720**, and a forceps-driving motor **730**.

For the assembly sequence of the forceps **400** structured as above, the folded portion **712** of the forceps-driving wire **710** inserted via the through-hole in the head **300** is wound on the exterior circumference of the driving roller **420**. The driving roller **420** is rotatably connected with the body **310**. The forcep jaws **410** on both sides are coupled with each other in such a fashion that the driving pins **421** of the driving roller **420** assembled on the body **310** are inserted into the guide slits **412**, respectively. Finally, the body **310** and the forcep jaws **410** are inserted into the head **300**, and a fixing shaft **311** is inserted into the body **310** and the pivot insertion openings **411** of the forcep jaws **410**.

Referring to FIGS. **13** and **17**, the forceps **400** configured as above are actuated by the forceps-driving unit **700**, which includes the forceps-driving wire **710**, the forceps-driving roller **720**, and the forceps-driving motor **730**.

The forceps-driving wire **710** is folded into two halves in such a fashion that a folded portion **712** passes through the hollow opening portion of the shaft **100** and the flexible joint **200** and surrounds the exterior circumference of the driving roller **420** engaged on the body **310** of the head **300**. Here, the opposite end of the forceps-driving wire **710** is connected with the forceps-driving roller **720** installed on the proximal

top end of the shaft **100**. The forceps-driving roller **720** can be turned by the forceps-driving motor **730**, thereby making the forceps-driving wire **710** rotate in one direction.

In the exemplary embodiment of the present invention, the laparoscopic surgical instrument having a small diameter shaft can be used as being connected with a slave robot (not shown) of a robot-assisted laparoscopic surgery (not shown). However, the present invention is not limited thereto, and can be used as a laparoscopic surgical instrument with a separated manipulating means attached thereto for an individually operated and manipulated laparoscopic surgery.

The operations of the laparoscopic surgical instrument having a small diameter shaft formed with the above mentioned figures in accordance with the present invention will be described more in detail.

Referring to FIGS. **8** and **14**, the longitudinal-driving motor **530** connected with the longitudinal-driving roller **520** needs to be rotated in order to turn the head **300** in the longitudinal direction by bending the flexible joint **200** in the longitudinal direction. The longitudinal-driving roller **520** connected with the longitudinal-driving motor **530** can turn at an angle of certain number of degrees in one direction by the turning power of the longitudinal-driving motor **530**. When the longitudinal-driving roller **520** turns in the clockwise direction, the left side of the longitudinal-driving wire **510** wound around the longitudinal-driving roller **520** can be wound around the longitudinal-driving roller **520** and the right side thereof can be unwound from the longitudinal-driving roller **520**. When the left side of the longitudinal-driving wire **510** contracts and the right side of the longitudinal-driving wire **510** extends in this manner, the flexible joint **200** is pressed to reduce the space between the head **300**, connected with the left side of the longitudinal-driving wire **510**, and the shaft **100**. The small rings **210** and the large rings **220** forming the flexible joint **200** are bent by downward pressure from above while drawing a circle. When the flexible joint **200** is bent while drawing a circle, the head **300** rotates to the left side of the longitudinal direction around the shaft **100**.

In order to turn the head **300** in the right side of the longitudinal direction, the longitudinal-driving motor **530** needs to rotate in the counterclockwise direction, contrary to the above motion. When the longitudinal-driving motor **530** rotates in the counter-clockwise direction, the longitudinal-driving roller **520** connected with the longitudinal-driving motor **530** turns in the counterclockwise direction, and the left side of the longitudinal-driving wire **510** wound around the longitudinal-driving roller **520** extends and the right side of the longitudinal-driving wire **510** contracts. When the length of the longitudinal-driving wire **510** changes based on the longitudinal-driving roller as above, the flexible joint **200** is bent to the right side of the longitudinal direction around the shaft **100** by the longitudinal-driving wire **510** and the head **300** turns to the right side.

The longitudinal-driving unit **500** enabling the flexible joint **200** to bend in the longitudinal direction can rotate the head **300** up and down by 90 degrees in the longitudinal direction.

Referring to FIGS. **9** and **15**, the transverse-driving motor **630** of the transverse-driving unit **600** is operated in order to bend the flexible joint **200** in the transverse direction. When the transverse-driving motor **630** rotates, the transverse-driving roller **620** can turn at an angle of a certain number of degrees in one direction and the transverse-driving wire **610** is wound around the transverse-driving roller **620**. When the transverse-driving roller **620** turns in the clockwise direction, the left side of the transverse-driving wire **610** can be wound

around the transverse-driving roller **620** and the right side of the transverse-driving wire **610** can be unwound. Consequently, the left side of the transverse-driving wire **610** can contract and the right side of the transverse-driving wire **610** can extend around the transverse-driving roller **620**, and the flexible joint **200** is pressed to reduce in the left direction between the head **300**, connected with the left terminal portion **611** of the transverse-driving wire **610**, and the shaft **100**. At this time, the small rings **210** and the large rings **220** forming the flexible joint **200** are bent in the left direction by downwards pressure while drawing a circle. The flexible joint **200** is bent in the left direction as above and the head **300** rotates to the left side of the transverse direction around the shaft **100**.

In order to turn the head **300** to the right side of the transverse direction, the transverse-driving motor **630** is rotated in the counterclockwise direction contrary to the above motion. When the transverse-driving motor **630** rotates in the counterclockwise direction, the left side of the transverse-driving wire **610** wound around the transverse-driving roller **620** extends and the right side of the transverse-driving wire **610** contracts. When the length of the transverse-driving wire **610** changes, the flexible joint **200** is bent to the right side and the head **300** can turn to the right side of the transverse direction around the shaft **100**.

The flexible joint **200** bending as above can rotate the head **300** by 90 degrees in the left/right side of the transverse direction around the extended axis of the shaft.

Referring to FIG. **16**, the flexible joint **200** bending in both longitudinal and transverse directions within 90 degrees, respectively, can be used together with the longitudinal-driving unit **500** and the transverse-driving unit **600**, and the head **300** can rotate 360 degrees in all directions around the shaft **100** when the longitudinal-driving unit **500** and the transverse-driving unit **600** are operated at the same time.

Referring to FIG. **17**, the forceps **400** formed on the head **300** can be actuated via turning of the forceps-driving roller **720** by rotating the forceps-driving motor **730**. When the forceps-driving roller **720** turns, one side of the forceps-driving wire **710** is wound around the forceps-driving roller **720** and the other side of the forceps-driving wire **710** is unwound. At this time, the folded portion **712** of the forceps-driving wire **710** rotates around the driving roller **420** and the driving roller **420** turns in the rotating direction of the forceps-driving wire **710**. When the forceps-driving roller **720** turns in the clockwise direction by using the forceps-driving motor **730**, the forceps-driving wire **710** rotates in the clockwise direction together with the forceps-driving roller **720**. At this time, the driving roller **420** rotatably connected with the folded portion **712** of the forceps-driving wire **710** can rotate in the clockwise direction together with the forceps-driving wire **710**. When the driving roller **420** turns in the clockwise direction as above, both forcep jaws **410** in which the guide slits **412** are connected with the driving pins **421** can be closed up until the opposing sides come into contact with each other by the rotation of the driving roller **420**.

In order to open the forcep jaws **410**, the forceps-driving roller **720** is turned in the counterclockwise direction. When the forceps-driving roller **720** turns in the counter-clockwise direction, the forceps-driving wire **710** also rotates in the counterclockwise direction and the driving roller **420** connected with the forceps-driving wire **710** also rotates in the counterclockwise direction, and both the forcep jaws **410**, in which the guide slits **412** are connected with the driving pins **421** of the driving roller **420**, are opened by moving in both directions.

As set forth above, it is to be appreciated that those skilled in the art can make substitutions, or change or modify the embodiments into various forms without departing from the scope and spirit of the present invention. Accordingly, the foregoing embodiments should be regarded as illustrative rather than limiting. The scope of the present invention is not defined by the detailed description as set forth above but by the accompanying claims of the invention. It should also be understood that all alterations or modifications derived from the definitions and scopes of the claims and their equivalents fall within the scope of the invention.

The invention claimed is:

1. A laparoscopic surgical instrument including a shaft and a head having a distal end to which a variety of surgical instruments are attached, the laparoscopic surgical instrument comprising:

- a flexible joint installed between the shaft and the head;
- a longitudinal-driving unit including a longitudinal-driving wire connected with both longitudinal ends of the head and a longitudinal-driving roller turning the longitudinal-driving wire, wherein the longitudinal-driving unit turns the flexible joint in a longitudinal direction;
- a transverse-driving unit including a transverse-driving wire connected with both transverse ends of the head and a transverse-driving roller turning the transverse-driving wire, wherein the transverse-driving unit turns the flexible joint in a transverse direction; and

forceps included or connected to the head, wherein the forceps include:

- a couple of forcep jaws separated to top and bottom sides and rotatably attached to the head at a pivot;
- a distal driving roller configured to rotate the forceps; and
- a forceps-driving unit configured to actuate the distal driving roller to turn the forceps, wherein each of the forcep jaws has a linearly elongated guide slit formed on an inside thereof that is elongated along an inclination away from the pivot, and

wherein the distal driving roller is rotatably coupled with a body connected with the head and has driving pins eccentrically protruded on both sides, each of the driving pins connected with the guide slit of each of the forcep jaws,

wherein the shaft has a small diameter, and

wherein the driving pins move in different directions in the guide slit according to a direction of rotation of the driving roller, and both forcep jaws are closed up until opposing sides come into contact with each other or are opened by moving in both directions.

2. The laparoscopic surgical instrument in accordance with claim 1, wherein the longitudinal-driving wire of the longitudinal-driving unit is partially wound on the longitudinal-driving roller, the transverse-driving wire of the transverse-driving unit is partially wound on the transverse-driving roller, and both ends of the longitudinal-driving wire and the transverse-driving wire are inserted into the shaft and extend through an outside of the flexible joint so as to be connected with the head.

3. The laparoscopic surgical instrument in accordance with claim 1, wherein the flexible joint includes a plurality of rings arranged in a row.

4. The laparoscopic surgical instrument in accordance with claim 3, wherein the plurality of rings comprises first rings and second rings larger than first rings alternately arranged in a row.

5. The laparoscopic surgical instrument in accordance with claim 4, wherein the first rings and the second rings larger than first rings are made of elastic material.

6. The laparoscopic surgical instrument in accordance with claim 4, wherein each of the second rings larger than first rings have guide grooves on outer exterior circumferential portions thereof that the longitudinal-driving wire and the transverse-driving wire are linearly inserted into the guide grooves.

7. The laparoscopic surgical instrument in accordance with claim 6, wherein the guide grooves are arranged in the outer exterior circumferential portions of the second rings larger than first rings at 90 degree intervals.

8. The laparoscopic surgical instrument in accordance with claim 3, further comprising an outer cover attached to an outside of the flexible joint so as to prevent the longitudinal-driving wire and the transverse-driving wire from moving out of the guide grooves of the second rings larger than first rings.

9. The laparoscopic surgical instrument in accordance with claim 8, wherein the instrument comprises a steel wire that is repeatedly wound into a coil shape with an equal diameter.

10. The laparoscopic surgical instrument in accordance with claim 1, wherein the forceps-driving unit includes:

- a forceps-driving wire inserted through the shaft, the flexible joint and a through-hole of the head, and having a folded portion wound on an exterior circumference of the distal driving roller;
- a forceps-driving roller provided on an upper portion of the shaft that a terminal portion of the forceps-driving wire is wound thereon; and
- a forceps-driving motor turning the forceps-driving roller.

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专利名称(译)	小口径腹腔镜手术器械		
公开(公告)号	US8702748	公开(公告)日	2014-04-22
申请号	US12/738478	申请日	2008-10-16
[标]申请(专利权)人(译)	金桐俊 俊园WOO JO张永		
申请(专利权)人(译)	金桐俊 俊园WOO JO张永		
当前申请(专利权)人(译)	国家癌症中心		
[标]发明人	KIM DONG JUN PARK JUN WOO JO YUNG HO		
发明人	KIM, DONG JUN PARK, JUN WOO JO, YUNG HO		
IPC分类号	A61B17/00		
CPC分类号	A61B19/22 A61B2017/2936 A61B2017/2932 A61B2019/2242 A61B2017/00398 A61B2017/2902 A61B2019/2249 A61B2017/2905 A61B34/70 A61B34/71 A61B34/72		
优先权	1020070104642 2007-10-17 KR		
其他公开文献	US20100280543A1		
外部链接	Espacenet USPTO		

摘要(译)

腹腔镜手术器械包括轴和头部，头部具有远端，各种手术器械附接到远端。腹腔镜手术器械还包括安装在轴和头部之间的柔性接头；纵向驱动单元，包括与所述头部的两个纵向端部连接的纵向驱动线和使所述纵向驱动线转动的纵向驱动辊；以及横向驱动单元，所述横向驱动单元包括与所述纵向驱动线的两个横向端部连接的横向驱动线。头部和横向驱动辊转动横向驱动线。纵向驱动单元在纵向方向上转动柔性接头，横向驱动单元在横向方向上转动柔性接头，并且轴具有小直径。

