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(54) **SURGICAL INSTRUMENT FOR ENDOSCOPIC SURGERY**

OPERATIONSINSTRUMENT FÜR ENDOSKOPISCHE CHIRURGIE

INSTRUMENT CHIRURGICAL POUR CHIRURGIE ENDOSCOPIQUE

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Description

OBJECT OF THE INVENTION

[0001] The present invention refers to a surgical instrument for endoscopic surgery which has its application in the field of medicine, and more specifically in those operations connected with endoscopic surgery in which an instrument is required that is capable of executing a double articulation in an element inserted in the interior of the body cavity of a patient in a precise way controlled simply with just one hand by a surgeon.

BACKGROUND OF THE INVENTION

[0002] In the field of medicine, the endoscopic approach route has now become consolidated for performing intra-cavity operations, which offers numerous advantages over the open surgery techniques used traditionally. Endoscopy, which comprises the visual examination of a cavity or duct of the organism, is usually applied as a technique that minimizes the invasion of the patient's body cavity and is carried out by means of the insertion of an endoscope by way of a minimal surgical incision through which the sheath passes housing the instrument. The incorporation of cold light and a video camera enables therapeutic manoeuvres to be carried out in the abdominal cavity, ranging from the simple collection of a biopsy to complete operations on the organs that it contains.

[0003] In the abdomen, the introduction of the endoscope and the instruments is usually done by way of rigid or semi-rigid sheaths that pass through the abdominal wall. During the operation they facilitate the replacement of the instruments without the loss of the gas that is used to keep the cavity distended, thanks to a built-in valve system.

[0004] Similarly, in the particular case of laparoscopic surgery, i.e. that endoscopic technique used for actuation in the abdominal cavity, the use of surgical instruments is normally required for the dissection by the surgeon of anatomical spaces of loose conjunctive tissue, for which different types of tweezers and separators are also used.

[0005] The design of instruments of this type to perform a surgical operation by endoscopy is usually determined by a series of functional requirements that the instrument has to be able to fulfil, such as manipulation in the body cavity from the exterior, permitting internal actuation on organs or tissues. For this purpose, these instruments must be capable of performing a series of movements controlled by the surgeon from the exterior. The handling of the instruments in these conditions reduces the operator's manoeuvring capability since he is unable to guide the instrument grasped in his hand, making use of all the joints of his upper limb. The point of penetration of the cannula through which the instrument is inserted into the cavity restricts its movement in the same way as an oar in relation to the rowlock that secures it to the hull of the

boat.

[0006] Accordingly, there is a tendency to incorporate articulated instruments that facilitate surgical manoeuvre instead of or as a supplement to traditional rigid instruments. These articulated instruments have different technical features depending on the surgery in which they are used and some of them are described below.

[0007] In United States Patent No. US 4,178,920, held by the institution 'American Hospital Supply Corporation', a urological instrument is defined that comprises a swivel element for use in cystoscopies, controlled manually by the operator, and which has a single element susceptible to be articulated for facilitating the introduction of a catheter in the mouth of a ureter. This instrument has a very limited application, since it is no use for dissection in spaces of difficult access or for those cases in which an instrument is required that simulates the movement that would be made by the surgeon's finger in open surgery operations. In addition, the articulated element is controlled directly, with no means of cushioning, so that the precision in the control of its movement is not very high, with the result that it proves rather rudimentary.

[0008] On the other hand, United States Patent No. US 5,366,479, applied for by the institution 'United States Surgical Corporation', describes another type of instrument used in endoscopy, which consists of a surgical stapler which, as in the previous case, has an area for gripping it, in the form of a handle, while coupled to this area there is a hollow rod-like element which has an articulated element at its free end that has its rotation in relation to an axis permitted in both directions. This instrument is used in surgery for applying staples, which are housed in a space in the interior of said hollow rod.

[0009] Now, although this instrument permits the rotation of the articulated element in both directions on account of its technical features and its configuration, it presents the same problems as the above-mentioned instrument, as it only permits a rotation movement of the swivel element, i.e. it only comprises one articulation and its use is limited as its purpose is strictly that of setting lines of staples in place for the occlusion of a specific segment of the digestive tube.

[0010] Similar articulated instruments to those referred above can be found in the following documents:

[0011] United States patent No. US-5549636-A discloses a surgical apparatus including a support rod having proximal and distal ends; at least one articulated finger at the distal end of the support rod; a handle at the proximal end of the support rod, the handle having a finger grip adapted to be actuated by the hand of a user; a connecting member connecting the finger grip and the finger; a thumb being disposed at the distal end of the support rod opposite the finger, a spring biasing the finger toward a retracted position; and the finger being responsive to a tension in the connecting member exerted by movement of the finger grip whereby the finger moves in a defined manner toward the thumb for grasping an object. The two-part form of claim 1 is based on this docu-

ment.

[0012] Likewise, United States patent application No. US-2005203561-A discloses a surgical dissector comprising an elongate shaft having a proximal end and a distal end. A blunt dissection tip is positioned on the distal end of the elongate shaft. A light source emits a diffuse visible energy, such as white light, from the blunt tip. The shaft may take a variety of shapes, including being rigid, flexible, malleable, straight, bent, curved, articulated, and/or segmented. In addition, the shaft may include one or more functional components. The dissector can be used to locate the dissector tip by observing the visible energy passing through tissue.

[0013] Furthermore, United States patent No. US-5807376-A refers to an apparatus provided for performing surgical tasks during laparoscopic procedures which includes an elongated body, a mechanical hand operatively associated with a distal portion of the elongated body and including a plurality of articulated fingers, and an actuation assembly operatively associated with the proximal portion of the elongated body for controlling the operation of the mechanical hand.

[0014] On the other hand, there exists a wide variety of instruments for many different purposes wherein the articulation of elements is required. In this sense, there is already known movable fingers for prostheses as disclosed in the European patent application No. EP-1195151-A1. Said document discloses a movable finger for prostheses, having a base disposed between the back and the palm of a hand, a first intermediate portion connected to the base, a second intermediate portion connected to the first intermediate portion, and a fingertip connected to the second intermediate portion, comprises: a first intermediate portion bending mechanism for actuating an actuator disposed in the base to pull a first wire to turn an eccentric member, pulling and bending the first intermediate portion by the eccentric member through a first intermediate portion pulling spring, and straightening it by a first intermediate portion straightening spring; a second intermediate portion bending mechanism for pulling a second wire wound around a pulley disposed as a movable pulley in the first intermediate portion by the eccentric member, pulling and bending the second intermediate portion by a third wire connected to the pulley and straightening it by a second intermediate portion straightening spring; and a fingertip bending mechanism for pulling and bending a fingertip by a fourth wire connected to the first intermediate portion, and pulling and straightening it by a fifth wire, which is connected to the first intermediate portion and drawn around through a route different from that of the fourth wire.

DESCRIPTION OF THE INVENTION

[0015] The present invention refers to a surgical instrument for endoscopic surgery which permits the execution of movements that emulate those performed by a surgeon's finger in open surgery operations, by means of a

double articulation, all this in an easy and precise way, controlled simply by the surgeon with just one hand, in order to obtain, for instance, the mechanical emulation of the movements of dissection of anatomical spaces of loose conjunctive tissue.

[0016] In view of its features, the surgical instrument proposed by the invention has a special application in operations performed on both the upper and lower abdomen, using the endoscopic route. In the case of operations on the upper abdomen it is applicable, for example, in cholecystectomy or in gastroesophageal fundoplication, in gastrectomy or in nephrectomy. In the case of operations on the lower hemiabdomen, the instrument is used to carry out the dissection of the preperitoneal space in the repair of a inguinal hernia, in iliac lymphadenectomy or in prostatectomy, for which the instrument is required to emulate the movements of a finger, so that it is best for these to be performed mechanically on account of the recurrence of the gestures.

[0017] In order to meet the above-mentioned functional requirements, the instrument that is the object of the invention comprises a handle, which has an appropriate configuration for it to be gripped and handled by the surgeon with just one hand. Attached to it there is a rigid tube, which is the invasive part of the instrument, at the distal end of which it has a first phalanx articulated in relation to the end of said rigid tube. Said first phalanx has, in turn, a second phalanx articulated at its distal end, the articulation movement of the second phalanx being linked to the articulation movement of the first phalanx by means of cables housed in cross ducts, emulating in this way the articulation movement of a human finger.

[0018] The instrument is held by the handle with a single hand, being controlled by means of placing preferably two fingers, such as for instance the index and middle finger, on a controller located in an area adjacent to the handle, in the form of a trigger, on which an axial movement may be made either by pulling or pressing said controller.

[0019] The interior of the handle holds at least a spring, or some other equivalent cushioning element that regulates and increases the precision of the movement of the controller, which actuates an operating fork, which in turn actuates a transmission rod, which undergoes linear forward movement, said transmission rod being connected to a link, which is in turn connected by its opposite end to the first phalanx.

[0020] In this way, when the surgeon actuates the controller, this operates the transmission rod by way of the fork, causing it to make a linear forward movement inside the rigid tube, while at the same time operating in turn the end of the transmission rod and the link, which is what produces a bending movement in the first phalanx, which swivels in relation to a first axis of rotation.

[0021] The movement of a second phalanx takes place as a result of the swivel movement of the first phalanx on account of the connection that exists between them, so the second phalanx cannot execute a movement sep-

arately from the first phalanx, i.e. without this being articulated. The instrument therefore comprises the disposition of cables linking the area of the distal end of the rigid tube, in which these are fixed by means of anterior anchoring holes, with the area of the proximal end of the second phalanx, in which they are fixed by means of end anchoring holes, said cables being crossed by means of cross ducts located in the interior of the first phalanx.

[0022] By means of the cross cable ducts the second phalanx is successfully connected to the first phalanx, with the result that the movement of this produces a relative movement of the second phalanx in relation to the first phalanx, so that an articulation takes place in respect of a second axis of rotation, located at the distal end of the first phalanx, produced by the actuation of the cables situated on the opposite side to the direction of rotation, which, through being crossover, produces an actuation on the side of the direction of rotation of the second phalanx, acting inversely when the first phalanx recovers its non-articulated position, which constitutes a movement that emulates the articulation movement performed by the phalanxes of a human finger.

[0023] Furthermore, in order to endow the instrument with a superior precision and range of positions, which affords it a greater versatility, the whole rigid tube is provided with the possibility of turning from its position on its own axis in relation to the fixed portion or handle. This is achieved by means of a rotation crown which is situated in the area of the handle provided for the attachment of said rigid tube. The possibility is contemplated of having a mechanism in the interior of said rotation crown comprising at least a spring, or some other equivalent means of cushioning, which permits the rigid tube to be locked or unlocked in a given position after being turned, at the surgeon's discretion, so that said rigid tube, which can turn through 360°, is endowed with complete freedom of rotation while maintaining all the functions and capabilities of the instrument.

[0024] The possibility is also contemplated of having an initial positioning or neutral wheel in the area of actuation of the fork with the transmission rod. By turning it we can adjust its position in relation to the transmission rod, so that, given the position of the fork in respect of said initial positioning wheel, we achieve a given initial position in which the first phalanx and the second phalanx are articulated prior to the operation of the controller by the surgeon, when so required for a specific process.

[0025] In this way, the initial or neutral position of the first phalanx and of the second phalanx may be kept perfectly straight, without any articulation of same, or else an initial position of said phalanxes of the instrument with a given articulation; it is even possible to achieve the initial position, without acting on the controller, with a given articulation when the instrument is in the interior of the patient's body cavity, without the need to withdraw it, which proves extremely useful during the course of an operation.

[0026] In order to increase the versatility of the instru-

ment, as a variant the possibility is considered of providing an internal axial hole both in the rigid tube and in the first and second phalanx, which are connected to a duct in order to enable the tasks of irrigation and suction of liquids to be performed during surgery. The option is also contemplated of incorporating an electric or ultrasound scalpel, of the types known in the state of the art, at the distal end of the second phalanx, so that it may be used in such processes as haemostasis.

[0027] In the instrument that is the object of the invention it is considered incorporating elements that will enable it to be operated remotely, i.e. that allow it to be used from a distance, in telesurgery operations. For this the action of the forces exerted by the surgeon is replaced by a robot, providing the distal end of the rigid tube with sensors, which may consist of the disposition of extensometric gauges according to the three axes of three-dimensional space. Thus, they convert the forces that act on the instrument into electrical signals, providing information on the forces acting on the instrument, or else on the forces that the instrument is exerting on the patient, similar to the perception that the surgeon's hand would have if the instrument were being handled by him. This enables the magnitude of the forces and the direction of the movements made by the instrument to be regulated at all times.

[0028] Therefore, in accordance with the invention described, the surgical instrument for endoscopic surgery proposed by the invention represents an advance in the instruments for endoscopic surgery used heretofore and it resolves the problems explained above in a fully satisfactory way, in that it is a versatile instrument that is provided with a double articulation in order to permit access and its simple precise actuation from the exterior in those areas of the body cavity which are of difficult access in endoscopy, simulating the articulation of a human finger and facilitating a wide variety of movements of the invasive part of the instrument without the need to withdraw it from the patient's body cavity during the course of the operation.

DESCRIPTION OF THE DRAWINGS

[0029] In order to supplement the description being given and to assist a clearer understanding of the features of the invention, in accordance with a preferred specimen practical embodiment of the same, we adjoin as an integral part of said description, a set of drawings wherein there is represented, for informative and non-restrictive purposes, the following:

Figure 1.- It shows a perspective view of the surgical instrument for endoscopic surgery that is the object of the invention.

Figure 2.- It shows a perspective view, in which the outer surfaces are represented as transparent in order to show the interior elements, in which we may

observe a close view corresponding to the end area of the rigid tube as well as the first phalanx and the second phalanx of the instrument.

PREFERRED EMBODIMENT OF THE INVENTION

[0030] In the light of the afore-mentioned figures, it may be observed how in one of the possible embodiments of the invention, the surgical instrument for endoscopic surgery comprises a rigid tube (3), the distal end of which has a first phalanx (4) articulated in relation to a first axis of rotation (6), which, in turn, at its distal end, has a second phalanx (5) articulated in respect of a second axis of rotation (7).

[0031] The interior of the rigid tube (3) houses a transmission rod (11), which is connected at its distal end to a link (10), which in turn is also connected, by its opposite end, to the first phalanx (4), the actuation of this transmission rod (11) being what produces the articulation of the phalanxes (4) and (5) of the instrument.

[0032] The movement of the second phalanx (5) is linked to that of the first phalanx (4) by means of cables housed in cross ducts (12) situated in the interior of the first phalanx (4), which are fixed at the distal end of the rigid tube (3) by means of anterior anchoring holes (8), and at the proximal end of the second phalanx (5) by means of end anchoring holes (9).

[0033] The rigid tube (3) is attachable to a handle (1), which has a suitable configuration for the holding, gripping and handling of the instrument by the surgeon with only one hand. It has a controller (2), which, when operated, usually with the fingers, actuates a fork (14), which in turn actuates the transmission rod (11) for its operation.

[0034] The possibility is contemplated of having in the interior of the handle (1) at least a spring - not represented - or some other equivalent cushioning element, which regulates and increases the precision of the movement of the controller (2).

[0035] Furthermore, in order to endow the instrument with a superior precision and range of positions, the possibility is contemplated of permitting the turning of the rigid tube (3) on its own axis in relation to the handle (1) by means of a rotation crown (13), which is situated in the area of attachment between the handle (1) and the rigid tube (3).

[0036] The option is also considered of having in the interior of said rotation crown (13) a mechanism - not represented - comprising at least a spring, or some other equivalent means of cushioning, for locking the position of the rigid tube (3).

[0037] The possibility is also contemplated of having an initial positioning wheel (15) in the area of actuation of the fork (14) with the transmission rod (11), which permits the positional adjustment of the fork (14) in relation to the transmission rod (11), so that it permits the regulation of the initial position of articulation of the first phalanx (4) and of the second phalanx (5), prior to the operation of the controller (2) by the surgeon.

[0038] As a variant, the possibility is also considered of providing an internal axial hole both in the rigid tube (3) and in the first phalanx (4) and in the second phalanx (5), which permit their connection to a duct - not represented - in order to enable the tasks of irrigation and suction of liquids to be performed during surgery.

[0039] The option is also contemplated of incorporating the terminal of an electric or ultrasound scalpel, of the types known in the state of the art, at the distal end of the second phalanx (5), so that it may facilitate electrocoagulation haemostasis with the same instrument.

[0040] In the instrument, consideration is also given to incorporating elements that will enable it to be operated remotely in telesurgery operations, permitting the forces exerted by the surgeon for the actuation of the instrument to be applied by a robot, providing the distal end of the rigid tube (3) with sensors, which may consist of extensometric gauges according to the three axes of three-dimensional space, which convert the forces that act on the instrument into electrical signals, providing information on the forces that the instrument is exerting on the patient, thus enabling the magnitude of the forces and the direction of the movements made by the instrument to be regulated at all times.

[0041] The possibility is also considered of its being disposable and being made with the intention of its being used in one operation only. In this case the instrument would be sealed, not permitting its disassembly and therefore not permitting its correct resterilization for reuse.

[0042] In the light of this description and set of figures, an expert on the matter would be able to appreciate that the embodiments of the invention which have been described may be combined in numerous ways within the object of the invention. The invention has been described according to some preferred embodiments of same, but for an expert on the matter it will be evident that multiple variations may be introduced in said preferred embodiments without exceeding the object of the invention which is defined by the appended claims.

Claims

1. Surgical instrument for endoscopic surgery comprising a rigid tube (3), whose distal end has a first phalanx (4) articulated, which in turn, at its distal end, has a second phalanx (5) articulated, **characterised in that** the second phalanx (5) is linked to the rigid tube (3) by means of cables housed in cross ducts (12), situated in the interior of the first phalanx (4), linking the movement of the second phalanx (5) to that of the first phalanx (4).
2. Surgical instrument for endoscopic surgery according to claim 1, **characterised in that** the ends of the cables housed in the ducts (12) are fixed at the distal end of the rigid tube (3) by means of anterior anchor-

ing holes (8), and at the proximal end of the second phalanx (5) by means of end anchoring holes (9).

3. Surgical instrument for endoscopic surgery according to the previous claims, **characterised in that** the interior of the rigid tube (3) houses a transmission rod (11) which is connected at its distal end to a link (10), which is in turn connected, by its opposite end, to the first phalanx (4), whose articulation is produced by the actuation of the transmission rod (11). 5
4. Surgical instrument for endoscopic surgery according to the previous claims, **characterised in that** the rigid tube (3) is attachable to a handle (1), which has an appropriate configuration for the holding, gripping and handling of the instrument with just one hand by the surgeon. 10
5. Surgical instrument for endoscopic surgery according to the previous claims, **characterised in that** the handle (1) has a controller (2), for actuating the instrument articulation movement by the surgeon, which operates a fork (14), which in turn acts on the transmission rod (11). 15
6. Surgical instrument for endoscopic surgery according to the previous claims, **characterised in that** the interior of the handle (1) is provided with at least a spring, or some other equivalent cushioning element, for regulating and increasing the precision of the movement of the controller (2). 20
7. Surgical instrument for endoscopic surgery according to the previous claims, **characterised in that** the rigid tube (3) is enabled to rotate around its own axis in respect of the handle (1) by means of a rotation crown (13), which is situated in the coupling area between the handle (1) and the rigid tube (3). 25
8. Surgical instrument for endoscopic surgery according to the previous claims, **characterised in that** the rotation crown (13) houses a mechanism comprising at least a spring, or some other equivalent means of cushioning, for locking the position of the rigid tube (3). 30
9. Surgical instrument for endoscopic surgery according to the previous claims, **characterised in that** the area of actuation of the fork (14) with the transmission rod (11) is provided with an initial positioning wheel (15), which permits the positional adjustment of the fork (14) in relation to the transmission rod (11), for regulating the initial position of articulation of the first phalanx (4) and of the second phalanx (5), prior to the operation of the controller (2) by the surgeon. 35
10. Surgical instrument for endoscopic surgery accord-

ing to any of the previous claims, **characterised in that** the interior of the rigid tube (3), of the first phalanx (4) and of the second phalanx (5) has an internal axial hole, which is connected to a duct for the tasks of irrigation and suction of liquids during surgery.

11. Surgical instrument for endoscopic surgery according to any of the previous claims, **characterised in that** the distal end of the second phalanx (5) is configured to incorporate a terminal of an electric or ultrasound scalpel.
12. Surgical instrument for endoscopic surgery according to any of the previous claims, **characterised in that** it is disposable.
13. Surgical instrument for endoscopic surgery according to any of the previous claims, **characterised in that** the distal end of the rigid tube (3) incorporates sensors, which may consist of extensimetric gauges according to the three axes of three-dimensional space, which convert the forces that act on the instrument into electrical signals, providing information on the forces that the instrument exerts on the patient.
14. Surgical instrument for endoscopic surgery according to claim 13, **characterised in that** the actuation on the instrument is carried out by means of a robot so that the instrument may be actuated remotely in telesurgery operations.

Patentansprüche

1. Chirurgisches Instrument für eine endoskopische Operation umfassend ein starres Rohr (3), dessen distales Ende ein erstes Fingerglied (4) gelenkig angebracht aufweist, welches wiederum an seinem distalen Ende ein zweites Fingerglied (5) gelenkig angebracht aufweist, **dadurch gekennzeichnet, dass** das zweite Fingerglied (5) durch Kabel angeordnet in gekreuzten, in dem Inneren des ersten Fingerglieds (4) angeordneten Durchführungen (12) an dem steifen Rohr (3) befestigt ist, welche die Bewegung des zweiten Fingerglieds (5) mit der des ersten Fingerglieds (4) koppeln.
2. Chirurgisches Instrument für eine endoskopische Operation nach Anspruch 1, **dadurch gekennzeichnet, dass** die Enden der Kabel, welche in den Durchführungen (12) angeordnet sind, an dem distalen Ende des steifen Rohrs (3) mittels vorderer Verankerungsausnehmungen (8) befestigt sind, und an dem proximalen Ende des zweiten Fingerglieds (5) mittels Endverankerungsausnehmungen (9).
3. Chirurgisches Instrument für eine endoskopische

Operation nach den vorherigen Ansprüchen, **dadurch gekennzeichnet, dass** in dem Inneren des steifen Rohrs (3) eine Übertragungsstange (11) angeordnet ist, welche an ihrem distalen Ende mit einem Verbindungsstück (10) verbunden ist, welches wiederum durch sein gegenüberliegendes Ende mit dem ersten Fingerglied (4) verbunden ist, dessen Beweglichkeit durch die Betätigung der Übertragungsstange (11) erzeugt wird.

4. Chirurgisches Instrument für eine endoskopische Operation nach den vorherigen Ansprüchen, **dadurch gekennzeichnet, dass** das steife Rohr (3) an einem Griff (1) befestigbar ist, welcher eine geeignete Beschaffenheit für das einhändige Halten, Greifen und Bedienen des Instruments durch den operierenden Arzt aufweist.
5. Chirurgisches Instrument für eine endoskopische Operation nach den vorherigen Ansprüchen, **dadurch gekennzeichnet, dass** der Griff (1) eine Steuereinrichtung (2) für das Betreiben der Instrumentengelenkbewegung durch den operierenden Arzt aufweist, welche eine Gabel (14) steuert, welche wiederum auf die Übertragungsstange (11) einwirkt.
6. Chirurgisches Instrument für eine endoskopische Operation nach den vorherigen Ansprüchen, **dadurch gekennzeichnet, dass** das Innere des Griffs (1) mindestens eine Feder oder ein anderes äquivalentes Federungselement für die Regelung und Erhöhung der Präzision der Bewegung der Steuereinrichtung (2) aufweist.
7. Chirurgisches Instrument für eine endoskopische Operation nach den vorherigen Ansprüchen, **dadurch gekennzeichnet, dass** das steife Rohr (3) dazu eingerichtet ist, um um seine eigene Achse in Bezug auf den Griff (1) mittels eines Rotationskranzes (13) zu rotieren, der im Kopplungsbereich zwischen dem Griff (1) und dem steifen Rohr (3) angeordnet ist.
8. Chirurgisches Instrument für eine endoskopische Operation nach den vorherigen Ansprüchen, **dadurch gekennzeichnet, dass** der Rotationskranz (13) einen Mechanismus umfassend mindestens eine Feder oder andere äquivalente Mittel der Federung für die Verriegelung der Position des steifen Rohrs (3) aufnimmt.
9. Chirurgisches Instrument für eine endoskopische Operation nach den vorherigen Ansprüchen, **dadurch gekennzeichnet, dass** im Bereich der Betätigung der Gabel (14) mit der Übertragungsstange (11) ein Anfangspositionierrad (15) vorgesehen ist, welches die Positionseinstellung der Gabel (14) in

Bezug auf die Übertragungsstange (11) für die Einstellung der Anfangsposition der Beweglichkeit des ersten Fingerglieds (4) und des zweiten Fingerglieds (5) vor der Betätigung der Steuereinrichtung (2) durch den operierenden Arzt erlaubt.

10. Chirurgisches Instrument für eine endoskopische Operation nach einem der vorherigen Ansprüche, **dadurch gekennzeichnet, dass** das Innere des steifen Rohrs (3), des ersten Fingerglieds (4) und des zweiten Fingerglieds (5) eine innere axiale Ausnehmung aufweist, welche mit einer Durchführung für die Aufgaben der Spülung und des Absaugens von Flüssigkeiten während der Operation verbunden ist.
11. Chirurgisches Instrument für eine endoskopische Operation nach einem der vorherigen Ansprüche, **dadurch gekennzeichnet, dass** das distale Ende des zweiten Fingerglieds (5) dazu eingerichtet ist, eine Endeinrichtung eines Elektro- oder Ultraschallskalpells aufzunehmen.
12. Chirurgisches Instrument für eine endoskopische Operation nach einem der vorherigen Ansprüche, **dadurch gekennzeichnet, dass** es als Einwegartikel ausgebildet ist.
13. Chirurgisches Instrument für eine endoskopische Operation nach einem der vorherigen Ansprüche, **dadurch gekennzeichnet, dass** das distale Ende des steifen Rohrs (3) Sensoren aufweist, welche aus Extensometermessgeräten hinsichtlich der drei Achsen des dreidimensionalen Raums bestehen können, welche die Kräfte, die auf das Instrument einwirken, in elektrische Signale umwandeln, welche Informationen über die Kräfte enthalten, welche das Instrument auf den Patienten aufbringt.
14. Chirurgisches Instrument für eine endoskopische Operation nach Anspruch 13, **dadurch gekennzeichnet, dass** die Betätigung des Instruments durch einen Roboter ausgeführt wird, so dass das Instrument in einer Teleoperation fernbedient werden kann.

Revendications

1. Instrument chirurgical pour chirurgie endoscopique, comprenant un tube rigide (3) dont l'extrémité distale a une première phalange (4) articulée, qui à son tour, au niveau de son extrémité distale, a une seconde phalange (5) articulée, **caractérise en ce que** la seconde phalange (5) est reliée au tube rigide (3) au moyen de câbles logés dans des conduits transversaux (12) situés à l'intérieur de la première phalange (4) reliant le mouvement de la seconde phalange (5)

à celui de la première phalange (4).

2. Instrument chirurgical pour chirurgie endoscopique selon la revendication 1, **caractérisé en ce que** les extrémités des câbles logés dans les conduits (12) sont fixées au niveau de l'extrémité distale du tube rigide (3) au moyen de trous d'ancrage antérieurs (8) et au niveau de l'extrémité proximale de la seconde phalange (5) au moyen de trous d'ancrage d'extrémité (9). 5
3. Instrument chirurgical pour chirurgie endoscopique selon les revendications précédentes, **caractérisé en ce que** l'intérieur du tube rigide (3) loge une tige de transmission (11) qui est raccordée, au niveau de son extrémité distale, à une liaison (10) qui est à son tour raccordée, par son extrémité opposée, à la première phalange (4), dont l'articulation est produite par l'actionnement de la tige de transmission (11). 10
4. Instrument chirurgical pour chirurgie endoscopique selon les revendications précédentes, **caractérisé en ce que** le tube rigide (3) peut être fixé à une poignée (1) qui a une configuration appropriée pour que le chirurgien maintienne, saisisse et manipule l'instrument uniquement avec une main. 15
5. Instrument chirurgical pour chirurgie endoscopique selon les revendications précédentes, **caractérisé en ce que** la poignée (1) à un organe de commande (2) pour que le chirurgien actionne le mouvement d'articulation de l'instrument, qui actionne une fourche (14) qui agit à son tour sur la tige de transmission (11). 20
6. Instrument chirurgical pour chirurgie endoscopique selon les revendications précédentes, **caractérisé en ce que** l'intérieur de la poignée (1) est prévu avec au moins un ressort, ou un autre élément d'amortissement équivalent, pour réguler et augmenter la précision du mouvement de l'organe de commande (2). 25
7. Instrument chirurgical pour chirurgie endoscopique selon les revendications précédentes, **caractérisé en ce que** le tube rigide (3) est autorisé à tourner autour de son propre axe par rapport à la poignée (1) au moyen d'une couronne de rotation (13) qui est située dans la zone de couplage entre la poignée (1) et le tube rigide (3). 30
8. Instrument chirurgical pour chirurgie endoscopique selon les revendications précédentes, **caractérisé en ce que** la couronne de rotation (13) loge un mécanisme comprenant au moins un ressort, ou un autre moyen équivalent d'amortissement, pour bloquer la position du tube rigide (3). 35
9. Instrument chirurgical pour chirurgie endoscopique 40

selon les revendications précédentes, **caractérisé en ce que** la zone d'actionnement de la fourche (14) avec la tige de transmission (11) est prévue avec une roue de positionnement initial (15) qui permet l'ajustement positionnel de la fourche (14) par rapport à la tige de transmission (11), afin de régler la position initiale d'articulation de la première phalange (4) et de la seconde phalange (5), avant l'actionnement de l'organe de commande (2) par le chirurgien. 45

10. Instrument chirurgical pour chirurgie endoscopique selon l'une quelconque des revendications précédentes, **caractérisé en ce que** l'intérieur du tube rigide (3) de la première phalange (4) et de la seconde phalange (5) a un trou axial interne qui est raccordé à un conduit pour les fonctions d'irrigation et d'aspiration des liquides pendant la chirurgie. 50
11. Instrument chirurgical pour chirurgie endoscopique selon l'une quelconque des revendications précédentes, **caractérisé en ce que** l'extrémité distale de la seconde phalange (5) est configurée pour comprendre une borne d'un scalpel électrique ou à ultrasons. 55
12. Instrument chirurgical pour chirurgie endoscopique selon l'une quelconque des revendications précédentes, **caractérisé en ce qu'il** est jetable.
13. Instrument chirurgical pour chirurgie endoscopique selon l'une quelconque des revendications précédentes, **caractérisé en ce que** l'extrémité distale du tube rigide (3) comprend des capteurs qui peuvent se composer de jauges extensiométriques selon les trois axes de l'espace tridimensionnel, qui convertissent les forces qui agissent sur l'instrument en signaux électriques, fournissant l'information concernant les forces que l'instrument exerce sur le patient.
14. Instrument chirurgical pour chirurgie endoscopique selon la revendication 13, **caractérisé en ce que** l'actionnement sur l'instrument est réalisé au moyen d'un robot de sorte que l'instrument peut être actionné à distance lors d'opérations de téléchirurgie.

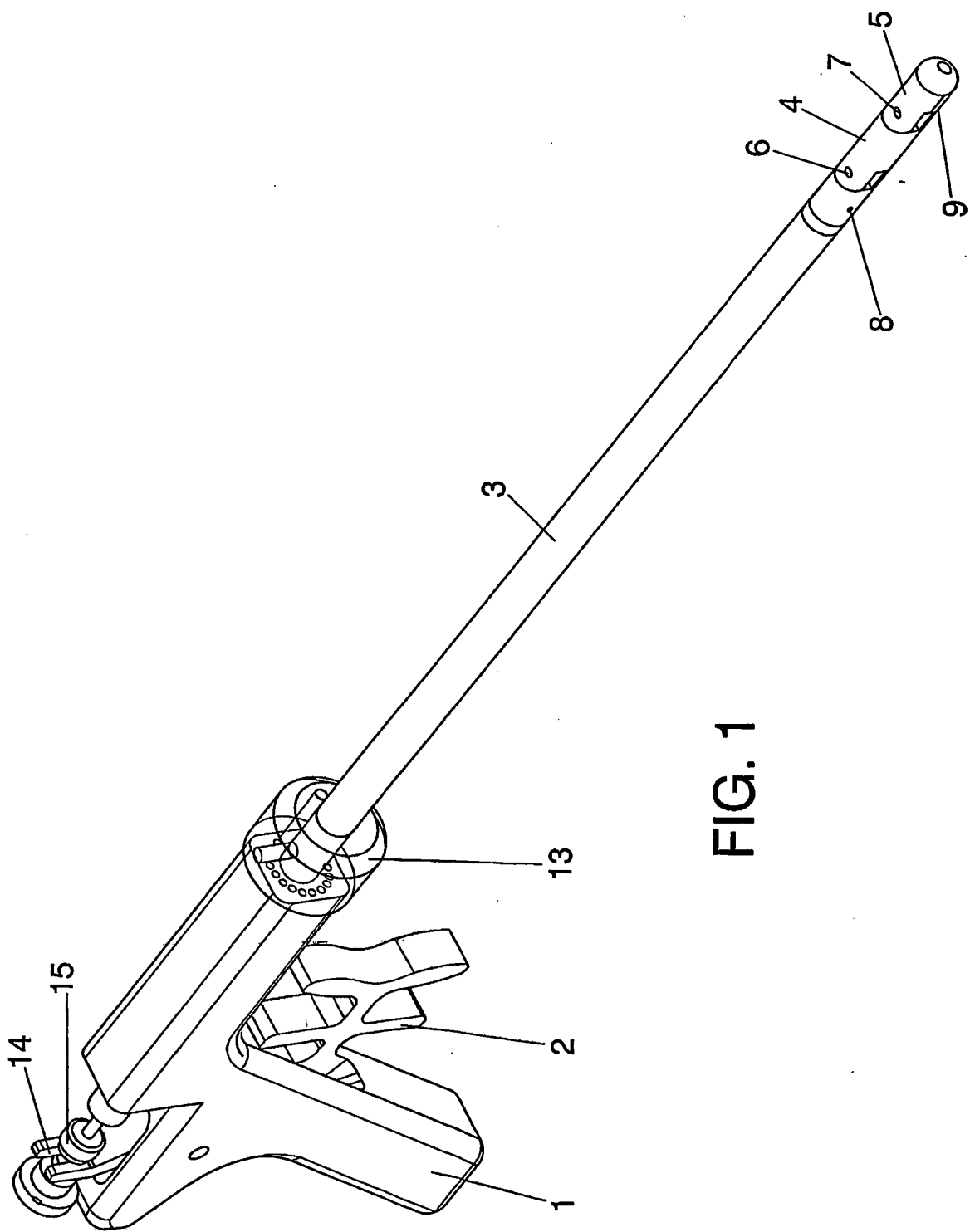


FIG. 1

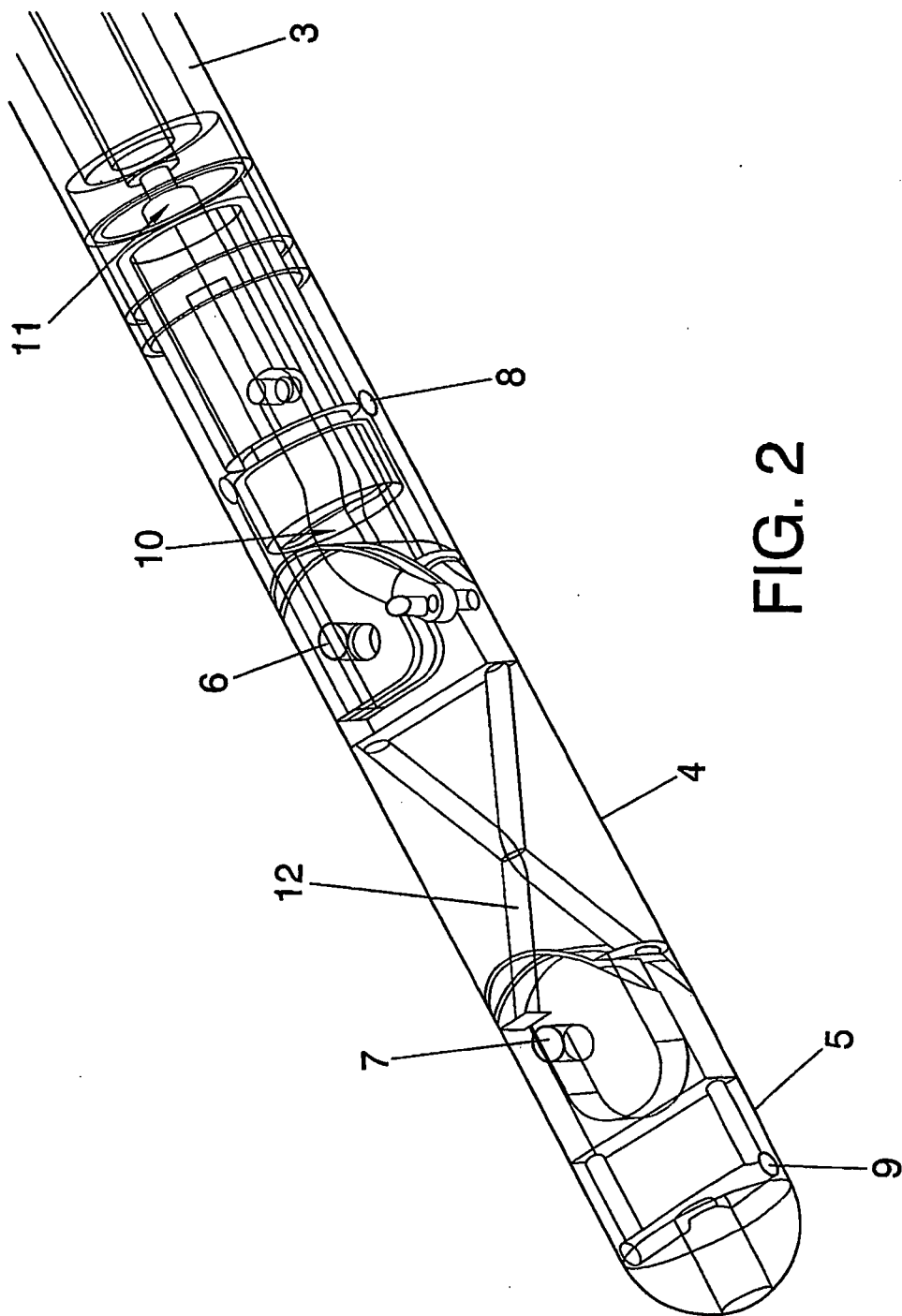


FIG. 2

REFERENCES CITED IN THE DESCRIPTION

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专利名称(译)	内窥镜手术的手术器械		
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申请(专利权)人(译)	CORPORACIO SANITARIA PARC·托利		
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优先权	2006000522 2006-03-03 ES		
其他公开文献	EP1994893A4 EP1994893A1		
外部链接	Espacenet		

摘要(译)

用于内窥镜手术的手术器械，其允许模拟外科医生手指的关节运动，包括刚性管（3），其远端具有铰接的第一指节（4），其又铰接到第二指节（5），通过容纳在第一趾骨（4）内部的交叉管道（12）中的电缆连接刚性管（3），将第二趾骨（5）的运动与第一趾骨的运动联系起来（如图4）所示，其铰接由于传动杆（11）的致动而发生，刚性管（3）可附接到手柄（1），手柄（1）包括控制器（2），用于通过其驱动器械关节运动。外科医生操作叉子（14），叉子又驱动传动杆（11）。

