

(19) World Intellectual Property
Organization
International Bureau

(43) International Publication Date
27 March 2014 (27.03.2014)



(10) International Publication Number
WO 2014/046618 A8

(51) International Patent Classification:

A61B 17/94 (2006.01) *A61B 19/00* (2006.01)
A61B 1/05 (2006.01) *B25J 18/06* (2006.01)
A61B 17/29 (2006.01)

(21) International Application Number:

PCT/SG2013/000408

(22) International Filing Date:

19 September 2013 (19.09.2013)

(25) Filing Language:

English

(26) Publication Language:

English

(30) Priority Data:

61/703,241 19 September 2012 (19.09.2012) US

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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, DK, DM, DO, DZ, EC, EE, EG, ES, FI, GB, GD, GE, GH, GM, GT, HN, HR, HU, ID, IL, IN, IS, JP, KE, KG, KN, KP, KR, KZ, LA, LC, LK, LR, LS, LT, 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.

(84) Designated States (unless otherwise indicated, for every kind of regional protection available): ARIPO (BW, GH, GM, KE, LR, LS, MW, MZ, NA, RW, SD, SL, SZ, TZ, UG, ZM, ZW), Eurasian (AM, AZ, BY, KG, KZ, RU, TJ, 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,

[Continued on next page]

(54) Title: FLEXIBLE MASTER - SLAVE ROBOTIC ENDOSCOPY SYSTEM

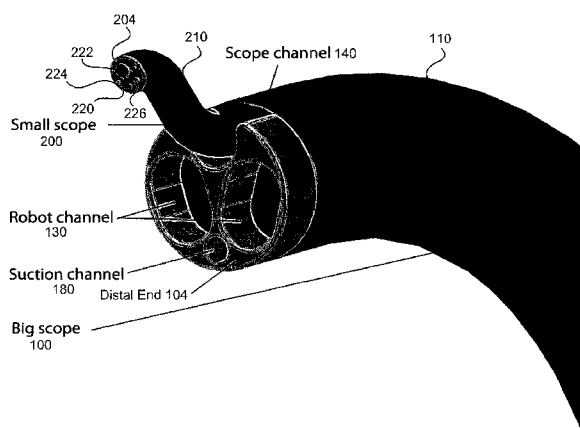


FIG. 3A

(57) Abstract: FIG. 3A: 140 Canal à endoscope 200 Endoscope de petite taille 130 Canal pour le robot 180 Canal d'aspiration 104 Extrémité distale 100 Endoscope de grande taille A master - slave robotic endoscopy system includes a flexible primary endoscope probe having at least one tool channel for carrying a tendon-sheath driven robot arm and corresponding end effector, and a secondary endoscope probe channel for carrying an imaging endoscope. The imaging endoscope provides enhanced image capture range relative to a distal end of the primary endoscope probe by way of a secondary endoscope probe channel distal opening proximally offset from the primary endoscope probe distal end; a ramp structure distally carried by the primary endoscope probe; and/or one or more actuatable distal imaging endoscope regions. Robot arms can include joint primitives that enable robot arm / end effector manipulation in accordance with intended degrees of freedom. A set of quick connect / disconnect interfaces couple an actuation controller to one or more actuation assemblies insertable into the tool channel(s), where each actuation assembly includes tendon-sheath elements, a robot arm, and its corresponding end effector.



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).

(48) Date of publication of this corrected version:

30 April 2015

Published:

— *with international search report (Art. 21(3))*

(15) Information about Corrections:

see Notice of 30 April 2015

Previous Correction:

see Notice of 2 April 2015