

Abstract

A surgical device or system (200), and a method are provided. The surgical system (200) may include an end-effector assembly (340) and an arm assembly (235, 330, 233, 360). The end-effector assembly (340) may include a first instrument assembly having a first instrument (342) and a first instrument driven portion (342a) configurable to be driven to move the first instrument (342) relative to a first axis (A). The arm assembly (330, 360) may include a first arm assembly body (330') and a second arm assembly body (360'), a first arm assembly joint portion (350) for joining the first and second arm assembly bodies (330', 360'), a first instrument drive assembly, and a first arm assembly drive assembly. The first instrument drive assembly may include a first integrated motor (332) and a first instrument drive portion (332a) controllable by the first integrated motor (332) to drive the first instrument driven portion (342a). The first arm assembly drive assembly may include a second integrated motor (339) and a first arm assembly drive portion (339a) controllable by the second integrated motor (339) to drive the first arm assembly body (330') to move relative to the second arm assembly body (360').

[Figure 5C]