



- (51) International Patent Classification:
A61B 34/00 (2016.01)
- (21) International Application Number:
PCT/IB2015/002533
- (22) International Filing Date:
18 December 2015 (18.12.2015)
- (25) Filing Language: English
- (26) Publication Language: English
- (30) Priority Data:
62/094,078 19 December 2014 (19.12.2014) US
- (71) Applicant: DISTALMOTION SA [CH/CH]; EPFL Innovation Park, Batiment I, 1015 Lausanne (CH).
- (72) Inventor; and
(71) Applicant : BEIRA, Ricardo Daniel Rita [PT/CH]; Avenue de Bethusy 55, 1012 Lausanne (CH).
- (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, IR, IS, JP, KE, KG, KN, KP, KR, 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.

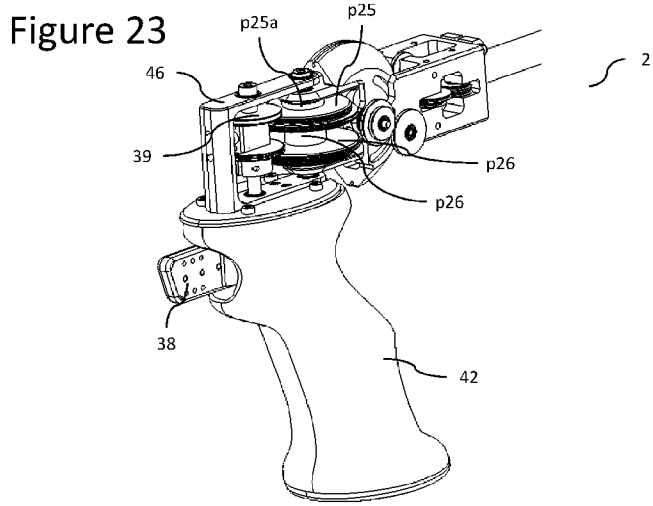
(84) Designated States (unless otherwise indicated, for every kind of regional protection available): ARIPO (BW, GH, GM, KE, LR, LS, MW, MZ, NA, RW, SD, SL, ST, SZ, TZ, UG, ZM, ZW), Eurasian (AM, AZ, BY, KG, KZ, RU, TJ, TM), European (AL, AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI, FR, GB, GR, HR, HU, IE, IS, IT, LT, LU, LV, 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).

Published:
— without international search report and to be republished upon receipt of that report (Rule 48.2(g))



WO 2016/097873 A2

(54) Title: ARTICULATED HANDLE FOR MECHANICAL TELEMANIPULATOR



(57) Abstract: Disclosed is a mechanical telemanipulator handle to control surgical instruments with articulated end-effectors, such as dissectors, scissors or graspers, enhancing a surgeon's performance during various surgical procedures. These surgical instruments may be inserted into surgical incisions in a body of a patient and the articulated end-effector is mounted on the distal extremity of the instrument shaft, comprising a plurality of links interconnected by a plurality of joints, whose movements are remotely controlled at the telemanipulator's proximal handle. This remote actuation is accomplished through mechanical transmission, optimally along flexible elements, which are able to kinematically connect the end-effector with the handle such that the movements applied on the handle are reproduced by the end-effector at a predetermined scaled ratio. The articulated handle further comprises one or more movement-amplification systems that amplify the movements generated at the handle so that the gripping force at the instrument's end-effector can be increased and the surgeon's ergonomics improved.

ARTICULATED HANDLE FOR MECHANICAL TELEMANIPULATOR

5 FIELD OF THE INVENTION

The present invention relates to the field of remotely actuated mechanical systems, more particularly to endoscopic mechanisms, and most particularly to remotely actuated endoscopic surgical instruments. More specifically, this invention relates to articulated handle mechanisms
10 used to control surgical instruments such as graspers, dissectors, and scissors, wherein the orientation of end-effectors in relation to the instrument shaft is able to be controlled. This mechanism is also adapted for any suitable remote actuated application requiring dexterous manipulation with high stiffness and precision such as, but in no way limited to, assembly manipulation, manipulation in narrow places, manipulation in dangerous or difficult
15 environments, and manipulation in contaminated or sterile environments.

BACKGROUND OF THE INVENTION

20 Open surgery is still the standard technique for most surgical procedures. It has been used by the medical community for several decades and consists of performing the surgical tasks through a long incision in the abdomen, through which traditional surgical tools are inserted. However, due to the long incision, this approach is extremely invasive for the patients, resulting in substantial blood loss during the surgery and long and painful recovery periods at
25 the hospital.

In order to reduce the invasiveness of open surgery, laparoscopy, a minimally invasive technique, was developed. Instead of a single long incision, four to five small incisions are made in the patient through which appropriately sized surgical instruments and endoscopic
30 cameras are inserted. Because of the low invasiveness, this technique reduces blood loss and shortens hospital stays and pain. When performed by experienced surgeons, this technique can attain clinical outcomes similar to open surgery. However, despite the above-mentioned advantages, laparoscopy requires extremely advanced surgical skills to manipulate the rigid and long instrumentation. The entry incision acts as a point of rotation, decreasing the surgeon's
35 freedom for positioning and orientating the instruments inside the patient. The movements of the surgeon's hand about this incision are inverted and scaled-up relative to the instrument tip

(“fulcrum effect”), which removes dexterity, sensibility and magnifies the tremors of the surgeon’s hands. In addition, these long and straight instruments force surgeons to work in a uncomfortable posture, which can be tremendously tiring during several hours of operation and result in stress and discomfort for hands, arms and body. Therefore, due to these drawbacks of laparoscopic instrumentation, these minimally invasive techniques are mainly limited to use in simple surgeries, while only a small minority of surgeons is able to use them in complex procedures.

To overcome these limitations, surgical robotic systems were developed to provide an easier-to-use approach to complex minimally invasive surgeries. By means of a computerized robotic interface, these systems enable the performance of remote laparoscopy wherein the surgeon sits at a console manipulating two master manipulators to perform the operation through several small incisions. Like laparoscopy, the robotic approach is also minimally invasive, bringing several advantages over open surgery in terms of reduced pain, blood loss, and recovery time. In addition, it also offers better ergonomics for the surgeon compared to open and laparoscopic techniques. However, although being technically easier, robotic surgery brings several negative aspects. A major disadvantage of these systems is related to the extremely high complexity of existing robotic devices, which are composed of complex mechanical and electronic systems, leading to huge costs of acquisition and maintenance, which are not affordable for the majority of surgical departments worldwide. Another drawback of these systems comes from the fact that current surgical robots are very large, competing for precious space within the operating room environment and significantly increasing preparation time. Access to the patient is thus impaired, which, together with a lack of force-feedback, raises safety concerns.

WO9743942, WO9825666 and US2010011900 disclose a robotic tele-operated surgical instrument, designed to replicate a surgeon’s hand movements inside the patient’s body. By means of a computerized, robotic interface, it enables the performance of remote laparoscopy wherein the surgeon sits at a console manipulating two joysticks to perform the operation through several small incisions. However, this system does not have autonomy or artificial intelligence, being essentially a sophisticated tool fully controlled by the surgeon. The control commands are transmitted between the robotic master and robotic slave by a complex computer-controlled mechatronic system, which is extremely costly to produce and maintain and difficult to use for the hospital staff.

WO2013014621 describes a mechanical telemanipulator for remote manipulation with a master-slave configuration, comprising a slave manipulator driven by a kinematically equivalent master manipulator and a mechanical transmission system such that each part of the slave manipulator mirrors the movement of each corresponding part of the master manipulator. Therefore, this system allows surgeons to perform surgical procedures by directly manipulating a control handle in the proximal part of the mechanical telemanipulator while their movements are replicated (scaled down or not) by an articulated instrument that can reach the abdominal cavity of the patient through small incisions or trocars. Although the mechanical transmission system is well adapted to the device, the kinematic model and transmission topology of the handle were not optimized, forcing surgeons to move their hands in non-ergonomic ranges of motion and limiting the amount of gripping force that can be generated at the instrument's end-effector.

Accordingly, an aim of the present invention is to provide a mechanical telemanipulator handle mechanism with a new configuration, which is able to deliver higher gripping forces to the instrument's end-effector.

Another aim of the present invention is to provide a mechanical telemanipulator handle mechanism with a more ergonomic range of motion for the surgeon's hands.

SUMMARY OF THE INVENTION

These aims and other advantages are achieved by a new articulated handle mechanism, designed to be used at the proximal extremity of a mechanical telemanipulator. This mechanical telemanipulator is intended to control surgical instruments, in the form of, for example, a dissector, scissor or grasper, with articulated distal end-effectors. These distal articulations of the end-effectors are able to (1) operate the surgical instrument in order to accomplish its "open/close" function (for example, grasping or cutting) and (2) provide orientation motions between the end effector and the instrument shaft. The handle corresponds to the distal degrees-of-freedom of the master manipulator and the end-effector corresponds to the distal degrees-of-freedom of the slave manipulator. The mechanical telemanipulator further comprises a mechanical transmission system arranged to kinematically connect all the master degrees-of-

freedom to the equivalent end-effector degrees-of-freedom such that the end-effector replicates the movements of the handle.

In order to deliver higher gripping forces to the instrument's end-effector and to provide a more ergonomic range of motion for the surgeon's hands, the handle comprises an amplification system configured to act on the two distal degrees-of-freedom. With this
5 amplification system, the angular relation between master and slave degrees-of-freedom is changed in some degrees of freedom. While for general degrees-of-freedom of the mechanical telemanipulator there is a "1 to 1" angular relation between a master joint and the equivalent slave joint, the angular relation between the two distal articulations of the handle and the two
10 distal articulations of the end-effector is modified only for the "open/close" function, while the angular relation for orientation motions remains "1 to 1". For the "open/close" function, the angular relation can be linearly amplified (for instance, "2 to 1" or "3 to 1") or non-linearly amplified, depending on the invention's embodiment.

15 BRIEF DESCRIPTION OF FIGURES

The invention will be better understood according to the following detailed description of several embodiments with reference to the attached drawings, in which:

- Figure 1 shows a perspective view of a mechanical telemanipulator according to an embodiment of the current invention;
- 20 - Figure 2 shows a schematic view of a mechanical telemanipulator according to an embodiment of the invention disclosed in WO2013014621;
- Figure 3 shows a perspective view of a mechanical telemanipulator comprising an articulated end-effector and an articulated handle according to an embodiment of the invention disclosed in WO2013014621;
- 25 - Figure 4 shows a perspective view of a distal end-effector of the mechanical telemanipulator according to an embodiment of the current invention and the invention disclosed in WO2013014621;
- Figure 5 shows a distal end-effector of the perspective of Figure 4 in a first active position;

- Figure 6 shows a distal end-effector of the perspective of Figure 4 in a second active position;
- Figure 7 shows a distal end-effector of the perspective of Figure 4 in a third active position;
- 5 - Figure 8 shows a distal end-effector of the perspective of Figure 4 in a fourth active position;
- Figure 9 shows a distal end-effector of the perspective of Figure 4 in a fifth active position;
- Figure 10 shows a perspective views of two distal end-effector links;
- 10 - Figure 11 shows the transmission topology for the two distal end-effector links, during an “opened” configuration, according to an embodiment of the invention disclosed in WO2013014621;
- Figure 12 shows the transmission topology for the two distal end-effector links, during an “closed” configuration, according to an embodiment of the invention disclosed in
15 WO2013014621;
- Figure 13 shows the transmission topology for the two distal end-effector links, during an “force-applying” configuration, according to an embodiment of the invention disclosed in WO2013014621;
- Figure 14 shows the transmission topology for a first distal end-effector link, according
20 to an embodiment of the current invention;
- Figure 15 shows the transmission topology for a second distal end-effector link, according to an embodiment of the current invention;
- Figure 16 shows a schematic side view of an articulated handle, according to an embodiment of the current invention;
- 25 - Figure 17 shows the transmission topology for two distal end-effector links, during an “opened” configuration, according to an embodiment of the current invention;
- Figure 18 shows the transmission topology for two distal end-effector links, during an “closed” configuration, according to an embodiment of the current invention;

- Figure 19 shows the transmission topology for two distal end-effector links, during an “force-applying” configuration, according to an embodiment of the current invention;
- Figure 20 shows the transmission topology for two distal end-effector links, during an “laterally oriented” configuration, according to an embodiment of the current invention;
- 5 - Figure 21 shows a first perspective view of an articulated handle, according to an embodiment of the current invention;
- Figure 22 shows a second perspective view of an articulated handle, according to an embodiment of the current invention;
- Figure 23 shows a third perspective view of an articulated handle, according to an
10 embodiment of the current invention;
- Figure 24 shows a fourth perspective view of an articulated handle, according to an embodiment of the current invention;
- Figure 25 shows the transmission topology for two distal end-effector links, during an “closed” configuration, according to an embodiment of the current invention;
- 15 - Figure 26 shows a schematic side view of an articulated handle, according to an embodiment of the current invention;
- Figure 27 shows the transmission topology for two distal end-effector links, during an “opened” configuration, according to an embodiment of the current invention;
- Figures 28 through 35 show motion transmission from first to the second amplification
20 pulleys by various mechanical means according to various embodiments of the current invention.
- Figures 36 and 37 show a schematic view of a different mechanical telemanipulator kinematics where embodiments of the current invention can be applied.
- Figure 38 shows the kinematics of a mechanical telemanipulator found in a hand-held
25 embodiment of the present invention.
- Figure 39 displays the kinematics of a single cable loop embodiment of the present invention.

DETAILED DESCRIPTION OF THE INVENTION

The articulated handle 2, according to an embodiment of the present invention, is intended to be used in a mechanical telemanipulator 1, like the one shown in Figure 1.

5 One of the key features of this type of mechanical telemanipulator 1 lies in its master-slave architecture, which enables a natural replication of the user hand movements, on a proximal handle 2, by a distal end-effector 3 on a remote location.

10 According to Figure 2, the mechanical telemanipulator 1 (according to an embodiment of the current invention and the invention disclosed in WO2013014621) may comprise: i) a master manipulator 4 having a corresponding number of master links 21, 22, 23, 24, 25, 26 interconnected by a plurality of master joints 9, 10, 11, 12, 13, 14, a ii) a handle 2 for operating the mechanical telemanipulator 1, connected to the distal end of the master manipulator 4, iii) a slave manipulator 5 having a number of slave links 27, 28, 29, 30, 31, 32 interconnected by a
15 plurality of slave joints 15, 16, 17, 18, 19, 20; and iv) an end-effector 3 (instrument/tool or a gripper/holder) connected to the distal end of the slave manipulator 5. More particularly, the kinematic chain formed by the plurality of articulated slave links 27, 28, 29, 30, 31, 32 and corresponding slave joints 15, 16, 17, 18, 19, 20 of the slave manipulator 5, may be substantially identical to the kinematic chain formed by the plurality of articulated master links 21, 22, 23,
20 24, 25, 26 and corresponding master joints 9, 10, 11, 12, 13, 14 of the master manipulator 4.

Referring still to Figure 2, the master manipulator 4 and the slave manipulator 5 are connected to each other by a connecting link 6. This connecting link 6 is connected to a ground 7 by a first telemanipulator joint 8. This first telemanipulator joint 8 can be decomposed in a
25 master joint 8m and slave joint 8s, which can respectively be considered as the first proximal joints of the master manipulator 4 and the slave manipulator 5. In the same way, the connecting link 6 can be decomposed in a master link 6m and slave link 6s, which can respectively be considered as the first proximal links of the master manipulator 4 and the slave manipulator 5.

30 The configuration of the mechanical telemanipulator can also be described by considering the end-effector 3 to be part of the slave manipulator 5 and the handle 2 to be part of the master manipulator 4. In a broader sense, the links and joints composing the end-effector can be considered distal slave links and joints, while the links and joints composing the handle can be considered distal master links and joints. Figure 3 shows a close-up view of the proximal

handle 2 and the distal end-effector 3, with their respective moving links (according to an embodiment of the invention disclosed in WO2013014621).

Referring to Figure 4, the end-effector 3 is connected to the distal extremity of the slave link 29 by a proximal joint, which allows the rotation of the proximal end-effector link 30 by the proximal axis 34 in such a manner that the orientation of the proximal end-effector link 30 with respect to the main axis 33 of the slave link 29 can be changed. The distal end-effector links 31, 32 are pivotally connected to the proximal end-effector link 30 by two distal joints, having coincident axes of rotation, which are represented by the distal axis 35. This distal axis 35 is substantially perpendicular and non-intersecting with the proximal axis 34 and substantially intersects the main axis 33 of the slave link 29. Figures 5 to 7 show the end-effector 3 with different angular displacements at the proximal end-effector link 30.

By actuating the two distal joints, the two distal end-effector links 31, 32 can be angulated over the distal axis 35, with respect to the plane containing the main axis 33 and the distal axis 35, by the angles θ_{31} , θ_{32} . Consequently, by the combination of rotations θ_{31} , θ_{32} , it is possible to operate the surgical instrument, in order to provide orientation motions between the end effector and the slave link 29 (Figure 8) and to accomplish its “open/close” function (Figure 9).

The mechanical telemanipulator 1 further comprises mechanical transmission systems arranged to kinematically connect the slave manipulator 5 with the master manipulator 4 such that the movement (angle of joint) applied on each master joint of the master manipulator 4 is reproduced by the corresponding slave joint of the slave manipulator 5.

For each degree of freedom of the mechanical telemanipulator 1, different types of mechanical transmissions can be used. In order to minimize the system’s overall friction and inertia, while increasing “back-drivability” and stiffness, the mechanical transmission between the majority of the master and slave joints is essentially in the form of pulley-routed flexible elements, where each driven pulley of the slave joint is connected to the respective driving pulley of the master joint, by a multi-stage closed cable loop transmission. As can be seen in Figure 4, the distal end-effector members 31, 32 are operatively connected to flexible members so that they can be independently rotated in both directions along the distal axis 35. The contact between the flexible elements and the distal end-effector elements is made in the circular

grooved surfaces 31a, 31b, 32a, 32b (Figure 10), which have a pulley-like geometry, forming the pulleys p31 and p32.

Figure 11 shows the working principle of this actuation for the case of transmitting the rotations θ_{25} , θ_{26} from the driving pulleys p25 (shaded in Figure 11) and p26 (not visible in Figure 11) around the axis 37, on the proximal handle 2, to the rotations θ_{31} , θ_{32} of the driven pulleys p31 (shaded in Figure 11) and p32 (not visible in Figure 11) around the axis 35, on the end-effector 3. The flexible element 36 is composed by two different segments, 36a, 36b, which form a closed cable loop between the driven pulley p31 of the end-effector link 31 and the driving pulley p25 of the handle link 25. The flexible element 37 (coincident with flexible element 36 in Figure 11) is composed by two different segments 37a, 37b, which form a closed cable loop between the driven pulley p32 end-effector link 32 (dashed in Figure 11) and the driving pulley p26 of the handle link 26 (dashed in Figure 11). These flexible elements 36, 37 connect the driving pulley 25p to the driven pulley 31p and the driving pulley 26p to the driven pulley 32p so that $\theta_{31} = \theta_{25}$ and $\theta_{32} = \theta_{26}$.

Figure 12 show the configuration where $\theta_{25} = \theta_{26} = 0$. In this case, $\theta_{31} = \theta_{32} = 0$, and the end-effector remains closed while no gripping force is being applied between the end-effector links 31 and 32. To increase the gripping force of the end-effector 3, the handle links 25 and 26, which are parallel but separated by an offset o (Figure 12), need to be further moved towards each other, by the angles θ_{25} , θ_{26} (Figure 13). These further movements stretch the segments 36a and 37b, which increases the force of the end-effector link 31 against the end-effector link 32. However, as can be seen in Figure 13, the amount of gripping force that can be achieved in this configuration, which is related to the rotation angles θ_{25} , θ_{26} , is geometrically limited by the physical collision between the handle links 25 and 26.

An articulated handle 2 able to overcome the above mentioned limitation is shown, inter alia, in Figures 14 to 27, according to different embodiments of the present invention. It comprises an amplification system that is introduced at the handle 2 level so that i) the rotations θ_{25} , θ_{26} are not physically limited (or the limitation allows for broader ranges of θ_{25} and θ_{26}) and ii) there is an amplification factor α between the rotation of the handle links 25 and 26 and the end-effector links 31 and 32, so that, when the end-effector links 31 and 32 are already in contact, the same movement of the handle links 25 and 26 will create a higher stretch on the

segments 36a and 37b, which therefore increases the gripping force at the end-effector (compared with the handle mechanisms shown in Figures 11 to 13).

Just like in the previous systems shown in Figures 11 to 13 (embodiments of
 5 WO2013014621), the driven pulley p32 is connected to the driving pulley p26 by the flexible
 element 37. However, in this solution, instead of being rigidly attached to the handle link 26,
 the driving pulley p26 is rigidly attached to a first amplification pulley p26a, which is connected
 to a second amplification pulley p26b by a handle flexible element 126. This second
 10 amplification pulley p26b is able to rotate around a second axis 40 and is rigidly attached to the
 replacement handle link 26', which replaces the handle link 26 from the system shown in
 Figures 11 to 13. The ratio between the diameters of second amplification pulley p26b and the
 first amplification pulley p26a correspond to the amplification factor α of the handle 2, which
 corresponds also to the ratio between the angle θ_{32} of the end-effector link 32 and the angle
 θ_{26}' of the replacement handle link 26' ($\theta_{32}/\theta_{26}' = \text{Op}26b/\text{Op}26a = \alpha$).

15

Figure 15 shows the previously described system applied to the actuation of the end-
 effector link 31. Just like in the previous systems shown in Figures 11 to 13, the driven pulley
 p31 is connected to the driving pulley p25 by the flexible element 36. However, in this solution,
 instead of being rigidly attached to the handle link 25, the driving pulley p25 is rigidly attached
 20 to a first amplification pulley p25a, which is connected to a second amplification pulley p25b
 by a handle flexible element 125. This second amplification pulley p25b is able to rotate around
 a second axis 40 and is rigidly attached to the replacement handle link 25', which replaces the
 handle link 25 from the system shown in Figures 13 to 15. The ratio between the diameters of
 second amplification pulley p25b and the first amplification pulley p25a correspond to the
 25 amplification factor α of the handle 2, which corresponds also to the ratio between the angle
 θ_{31} of the end-effector link 31 and the angle θ_{25}' of the replacement handle link 25'
 ($\theta_{31}/\theta_{25}' = \text{Op}25b/\text{Op}25a = \alpha = \theta_{32}/\theta_{26}' = \text{Op}26b/\text{Op}26a$).

Figure 16 shows the side view of an embodiment of the current invention where the
 30 replacement handle link 25' and replacement handle link 26' are merged in a single replacement
 handle link 38 and the second amplification pulley p25b and the second amplification pulley
 p26b are merged in a single second amplification pulley 39. As can be seen in Figure 17, this
 solution enables to simultaneously trigger the actuation to both the end-effector link 31 and
 end-effector link 32, with an amplification factor α ($\theta_{38} \cdot \alpha = \theta_{25} = \theta_{26}$).

Figure 18 shows the configuration where $\theta_{38}=0$. In this case, $\theta_{31}=\theta_{32}=0$, the end-effector remains closed while no gripping force is being applied between the end-effector links 31 and 32. To increase the gripping force of the end-effector 3, the replacement handle link 38 needs to be further moved towards the closing direction, by an angle θ_{38} (Figure 19). This movement stretches the segments 36a and 37b and therefore increases the force of the end-effector link 31 against the end-effector link 32. This stretching of the cables (and consequent increase in gripping force) is higher than in the configuration shown in Figure 13, due to the amplification factor α and by the fact that the two handle links 25, 26 are not physical colliding between them.

In order to provide orientation motions θ_{31} , θ_{32} between the end effector 3 and the slave link 29 (Figure 8), the structural element 46 is rotated by an angle θ_{37} , while the replacement handle link 38 remains stationary in relation to the structural element 46 (Figure 20). This structural element 46 is able to pivot around the handle axis 37 and is where the second amplification pulleys p25b, p26b are mounted to rotate around the axis 40. This causes the end-effector link 31 and the end-effector link 32 to move θ_{31} , θ_{32} in the same angle as θ_{37} , with no amplification ($\theta_{31}=\theta_{33}=\theta_{37}$). However, a second amplification factor α_2 could be used for these degrees of freedom.

Figures 21 to 24 show an embodiment of the handle 2 in different perspective views. A holder 42 may be attached to the handle 2 so that it can be more easily and ergonomically manipulated by the user.

While this invention has been shown and described with reference to particular embodiments thereof, it will be understood by those skilled in the art that various changes in form and details may be made therein without departing from the spirit and scope of the invention as defined by the appended claims. For instance, the replacement handle link 25' and replacement handle link 26' may not be merged (Figure 25) and the second axis 40, around which the second amplification pulley p26b is able to rotate, may be perpendicular and non-intersecting with the axis 37 (Figure 26). In another embodiment, there can be a spring element 43 that can bring the replacement handle link 38 to an opened default position (Figure 27).

In other embodiments, the rotation can be transmitted from first amplification pulleys p25a, p26a to the second amplification pulleys p25b, p26b by different mechanical solutions (Figures 28 to 33). In the previously described embodiments (Figures 14 to 27) the motion transmission is made by flexible elements l25a, l25b, l26a, l26b whose extremities are fixed to the first and second amplification pulleys p25a, p26a, p25b, p26b in a crossed (Figure 28) and uncrossed (Figure 29) configuration. In the embodiment of Figure 30, the motion transmission is made by the friction force between the first amplification pulley p25a, p26a and second amplification pulley p25b, p26b. In the embodiment of Figure 31, the motion transmission is made by a contact force (using teeth or other method to increase contact forces). In the embodiment of Figure 34, the motion transmission is made by a push-pull element 44, which is pivotally connected to the first amplification pulley p25a, p26a and second amplification pulley p25b, p26b. In the embodiment of Figure 35, the motion transmission is made by constant-pitch element 45 (which can take the form of a timing belt, a chain or a bead chain) that can engage the first amplification pulley p25a, p26a and second amplification pulley p25b, p26b. In still further embodiments, the embodiments previously described (Figures 28 to 33) can be used to transmit motion between non-circular first and second amplification pulleys p25a, p26a, p25b, p26b (Figure 34) or to transmit motion between eccentrically rotating first and second amplification pulleys p25a, p26a, p25b, p26b (Figure 35). In both the embodiments of Figures 32 and 33, non-constant amplification factors can be achieved.

20

In other embodiments, the mechanical telemanipulator 1 can assume other kinematics, like the ones shown in Figures 36, 37 and 38 (hand-held device).

In another embodiment of the current invention, instead of having multiple cable loops to actuate each degree-of-freedom, single cable loops 37 and 36 are directly connecting the driven pulleys p32 and p31 to the amplification pulley 39 (Figure 39). In this solution, the driving pulleys p26 and p25 are converted into idle pulleys i26 and i25 that are able to turn around the axis 37. In addition, the ratio between the diameters of the idle pulleys i26, i25 and the amplification pulley 39 correspond to the amplification factor α of the handle 2, which corresponds also to the ratio between the angles θ_{32} and θ_{31} of the end-effector link 32 and the angle θ_{38} of the replacement handle link 38 ($\theta_{32}/\theta_{38} = \alpha$; $\theta_{31}/\theta_{38} = \alpha$; $\phi_{i26}/\phi_{39} = \alpha$; $\phi_{i25}/\phi_{39} = \alpha$).

30

CLAIMS

1. An articulated handle for a mechanical telemanipulator comprising:
5 a plurality of handle links interconnected by a corresponding plurality of handle joints
mechanical transmission elements arranged to kinematically connect the articulated handle with an articulated end-effector comprising a plurality of end-effector links interconnected by a corresponding plurality of end-effector joints wherein movement applied to a first handle link is reproduced, at a predetermined amplification,
10 at a corresponding first end-effector link.
2. The articulated handle of claim 1, wherein movement applied to a second handle link is reproduced, at a second predetermined amplification, at a corresponding second end-effector link.
15
3. The articulated handle of claim 1, wherein the angular movement of a single handle link is able to be reproduced, with a predetermined amplification factor, by two different end-effector links, which rotate in opposite directions.
- 20 4. The articulated handle of claim 1, wherein movement transmission between a handle link and an end-effector link is accomplished by a single loop flexible transmission element, comprising a flexible element selected from the group consisting of wires, chains, ropes and belts.
- 25 5. The articulated handle of claim 1, wherein movement transmission between a handle link and an end-effector link is accomplished by a multi loop transmission element.
6. The articulated handle of claim 5, wherein a proximal stage of the multi loop transmission element comprises a rigid linkage mechanism.
30
7. The articulated handle of claim 5, wherein a proximal stage of the multi loop transmission element is accomplished by contact force between at least two mechanical elements.

8. The articulated handle of claim 7, wherein the contact force between the at least two mechanical elements is maximized by the use of teathed geometries.
9. The articulated handle of claim 1, wherein the predetermined amplification is consistent
5 with the movement applied to the first handle link.
10. The articulated handle of claim 1, wherein the predetermined amplification is inconsistent with the movement applied to the first handle link.
- 10 11. The articulated handle of claim 1, further comprising a spring element configured to bring the at least one handle link to a default position when it is not being actuated by a user and to bring the at least one end-effector link to a corresponding default position when the at least one handle link is not being actuated by the user.
- 15 12. The articulated handle of claim 1, further comprising a ratchet mechanism configured to selectively block the movement of the at least one handle link.
- 20 13. The articulated handle of claim 1, wherein the mechanical telemanipulator has a hand-held configuration, without any base support, so that a user can control movement of the articulated end-effector only by actuating the articulated handle.

Figure 1

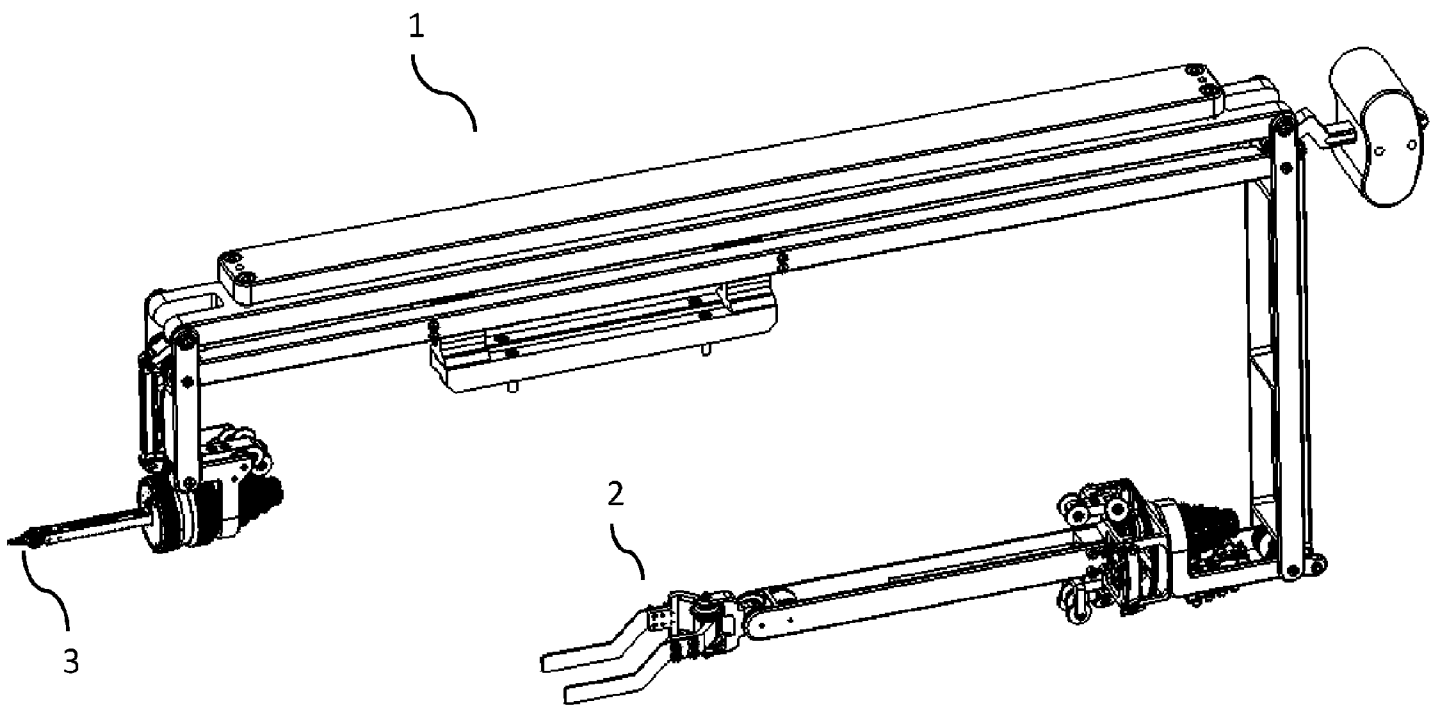


Figure 2

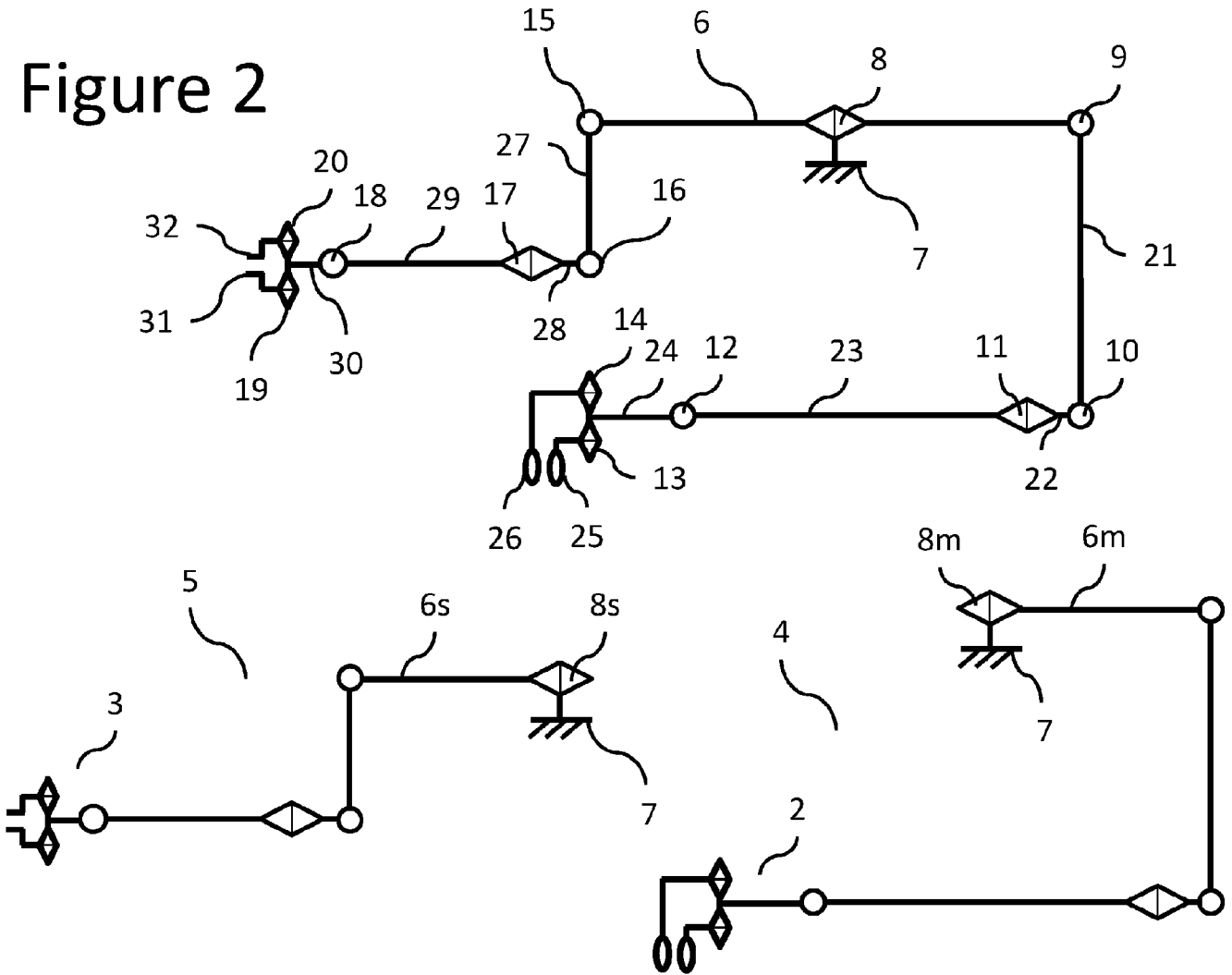


Figure 3

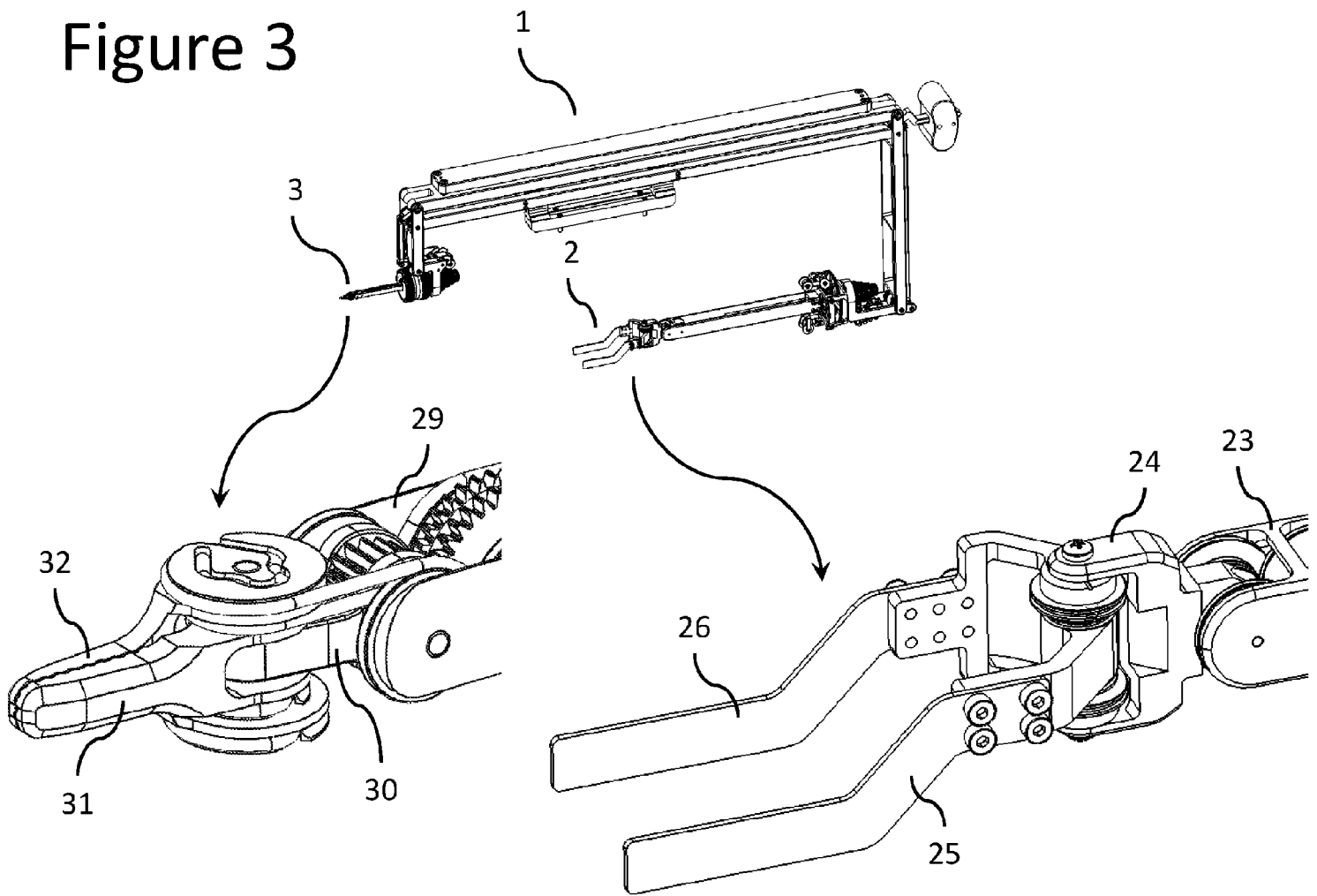


Figure 4

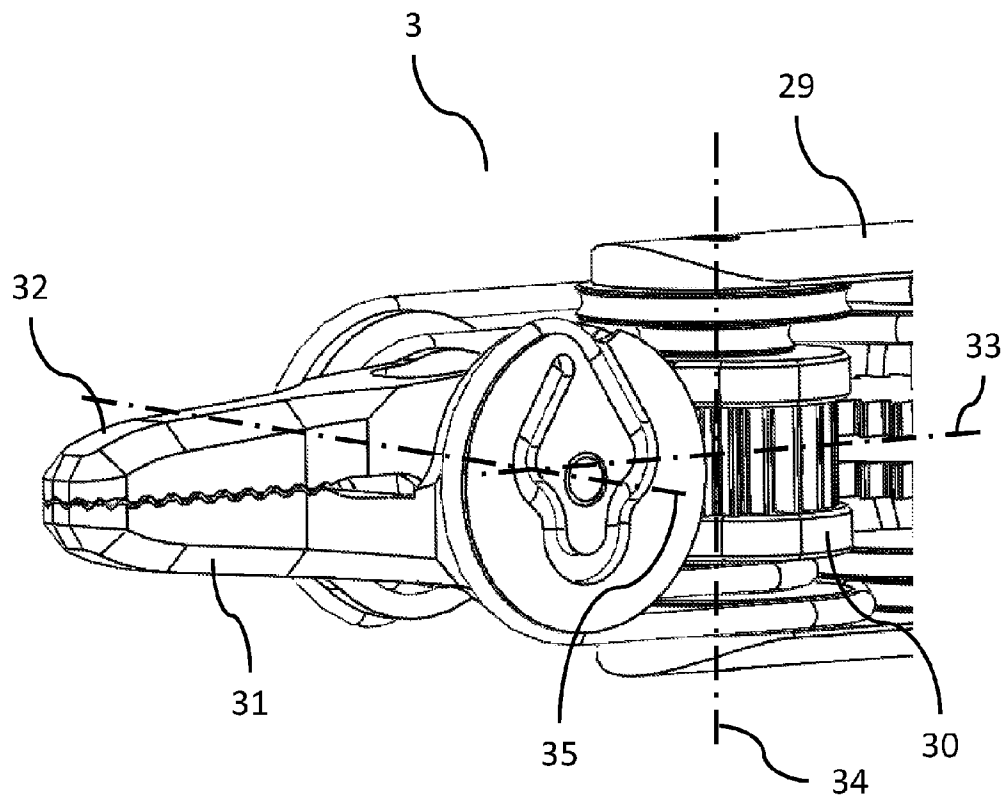


Figure 6

Figure 5

Figure 7

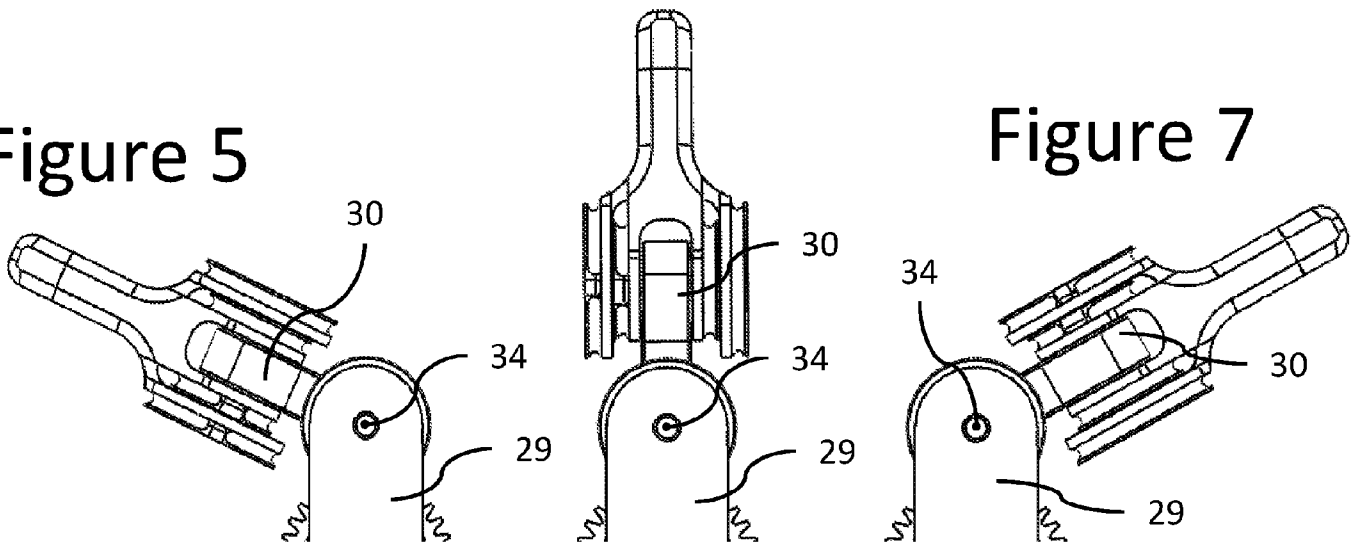


Figure 8

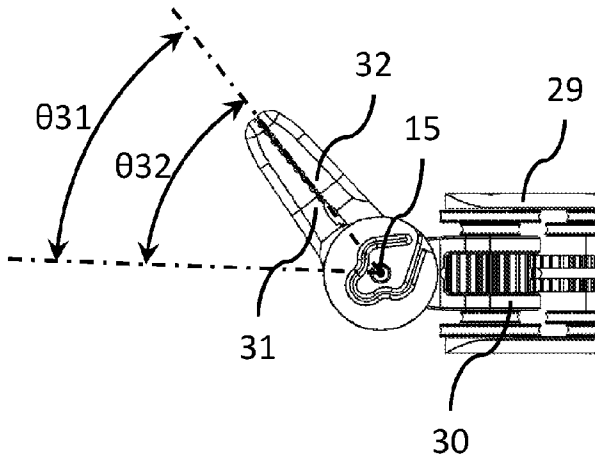


Figure 9

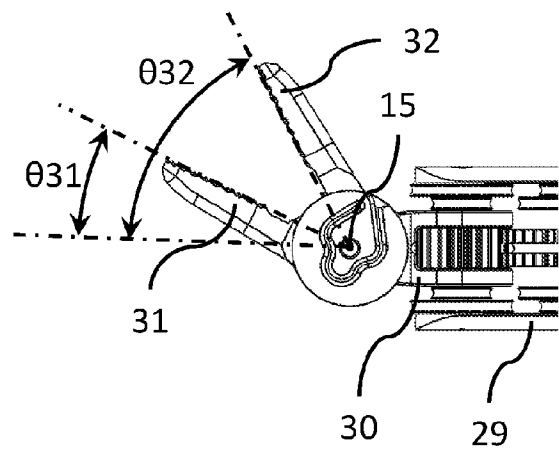


Figure 10

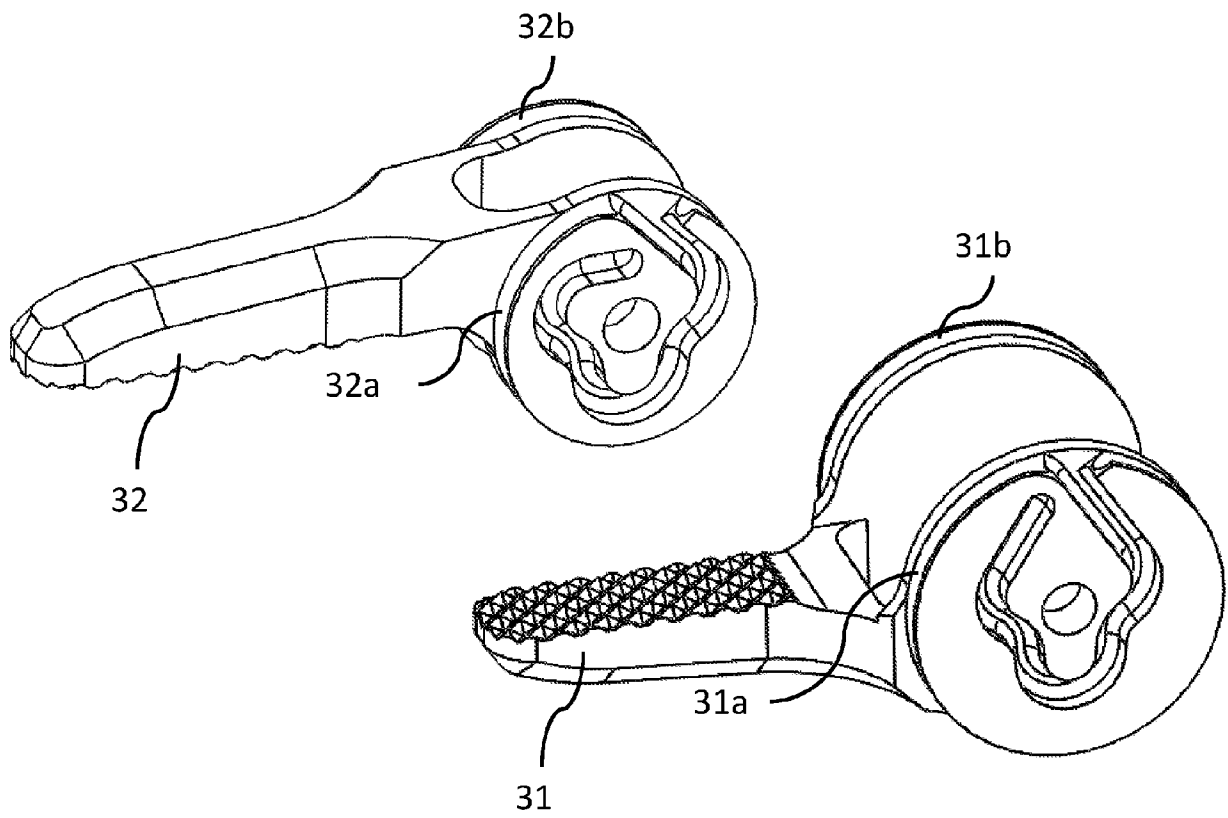


Figure 11

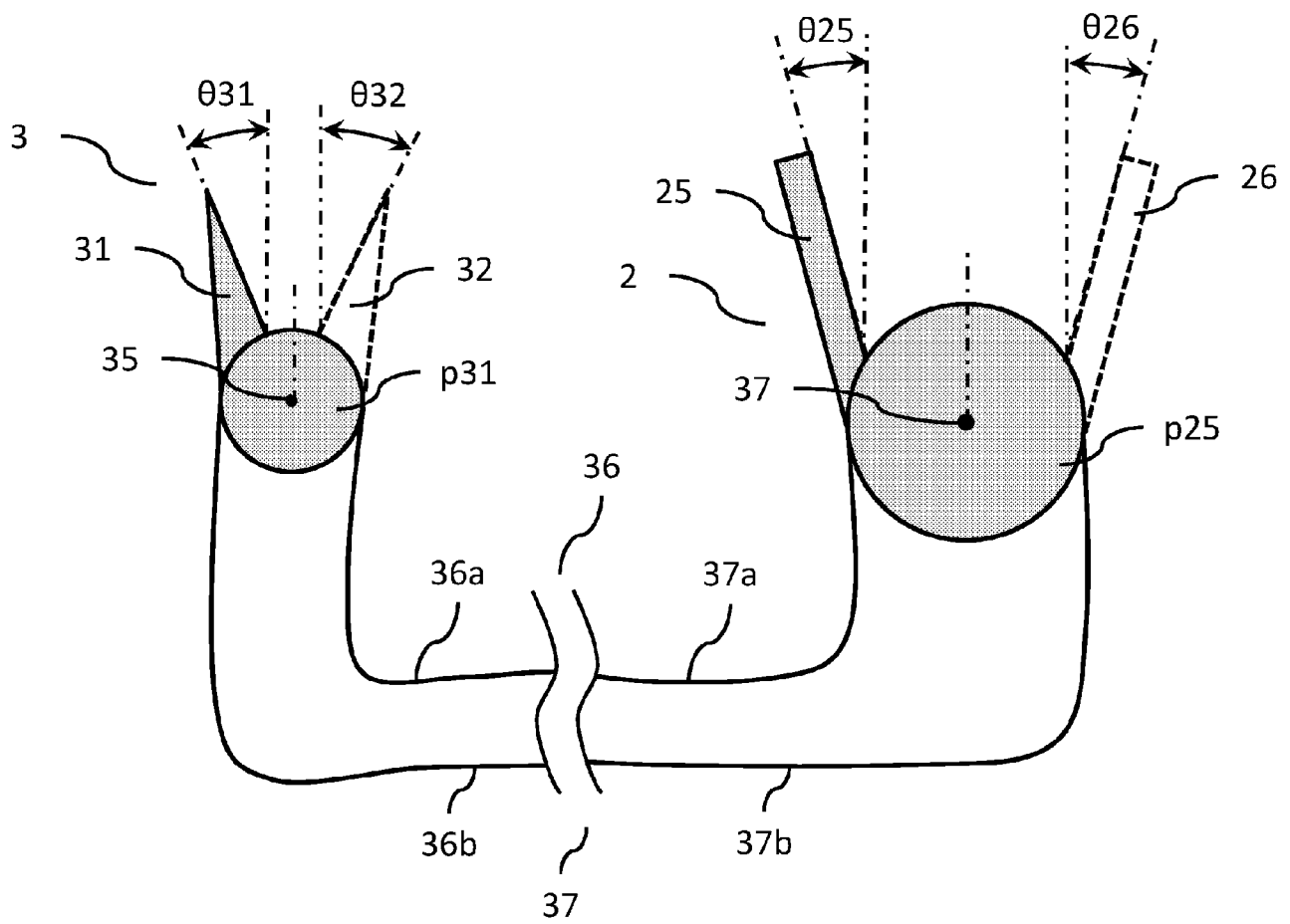


Figure 12

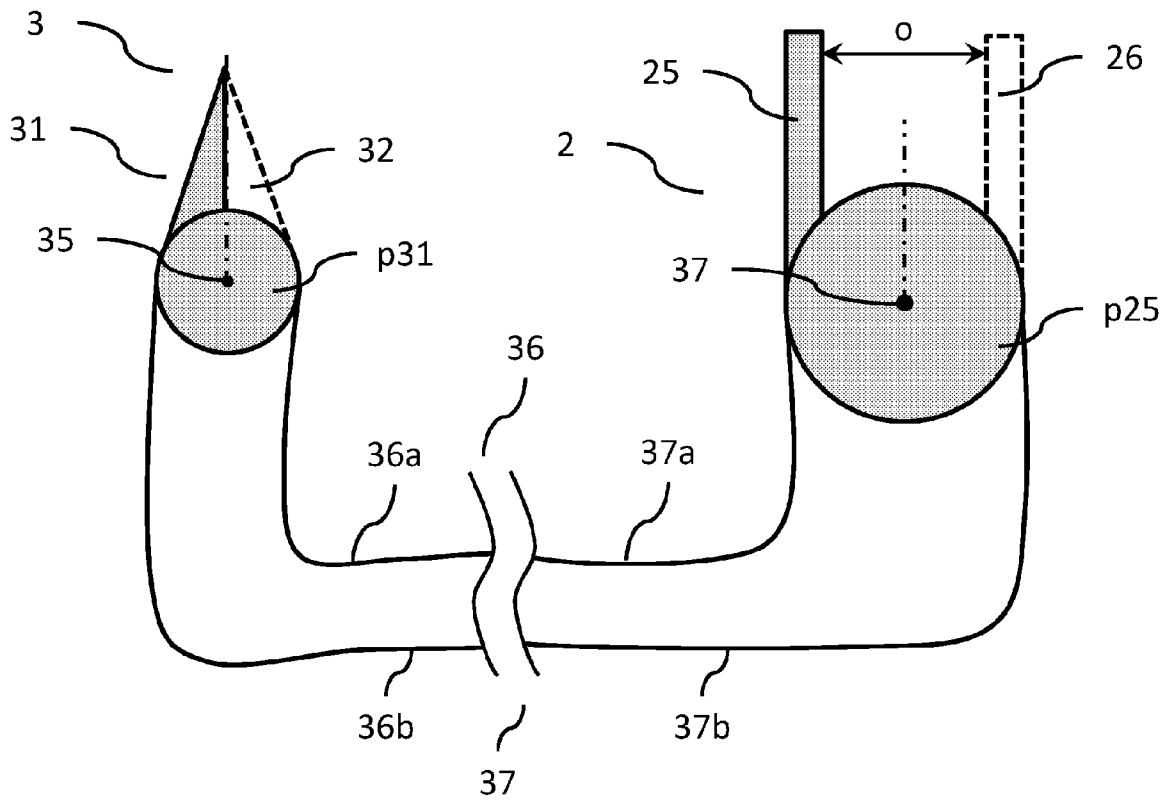


Figure 13

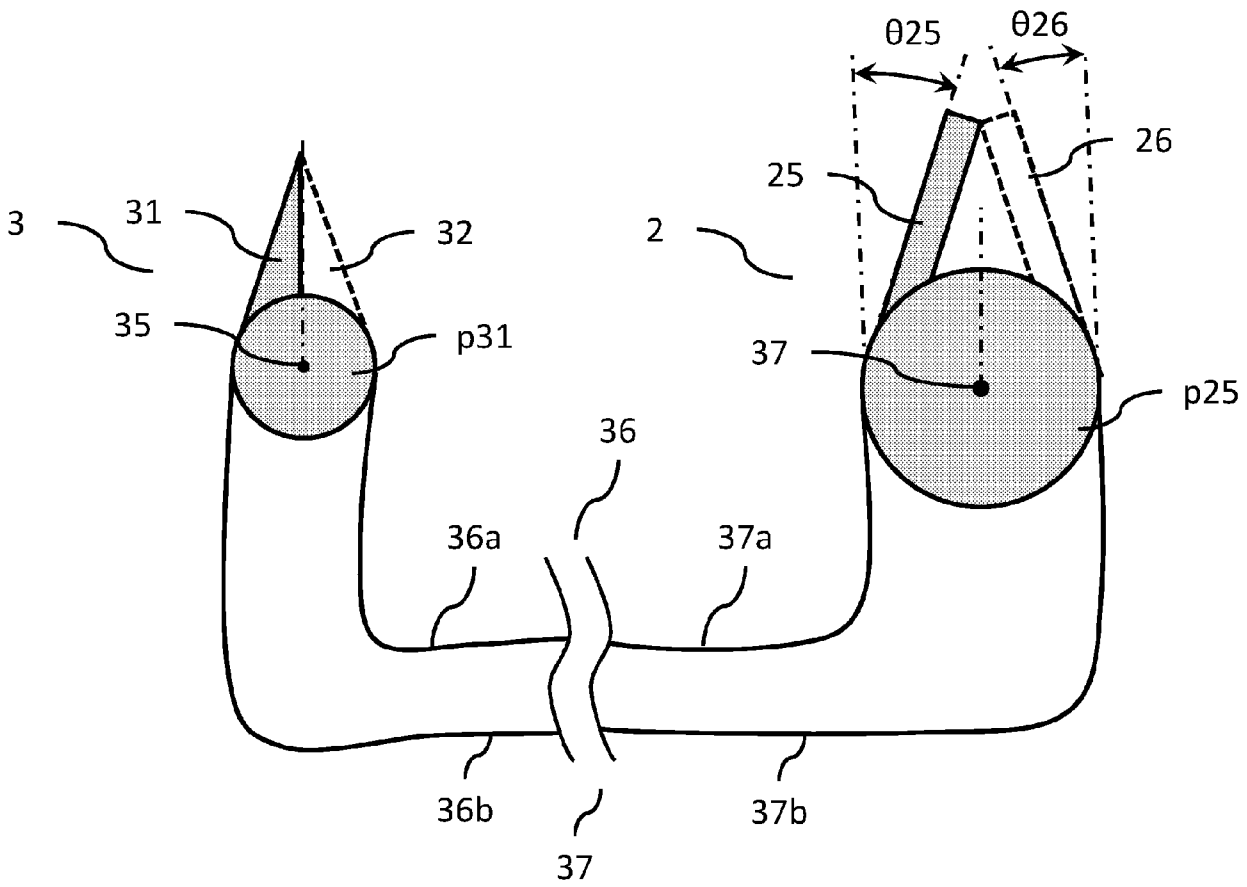


Figure 14

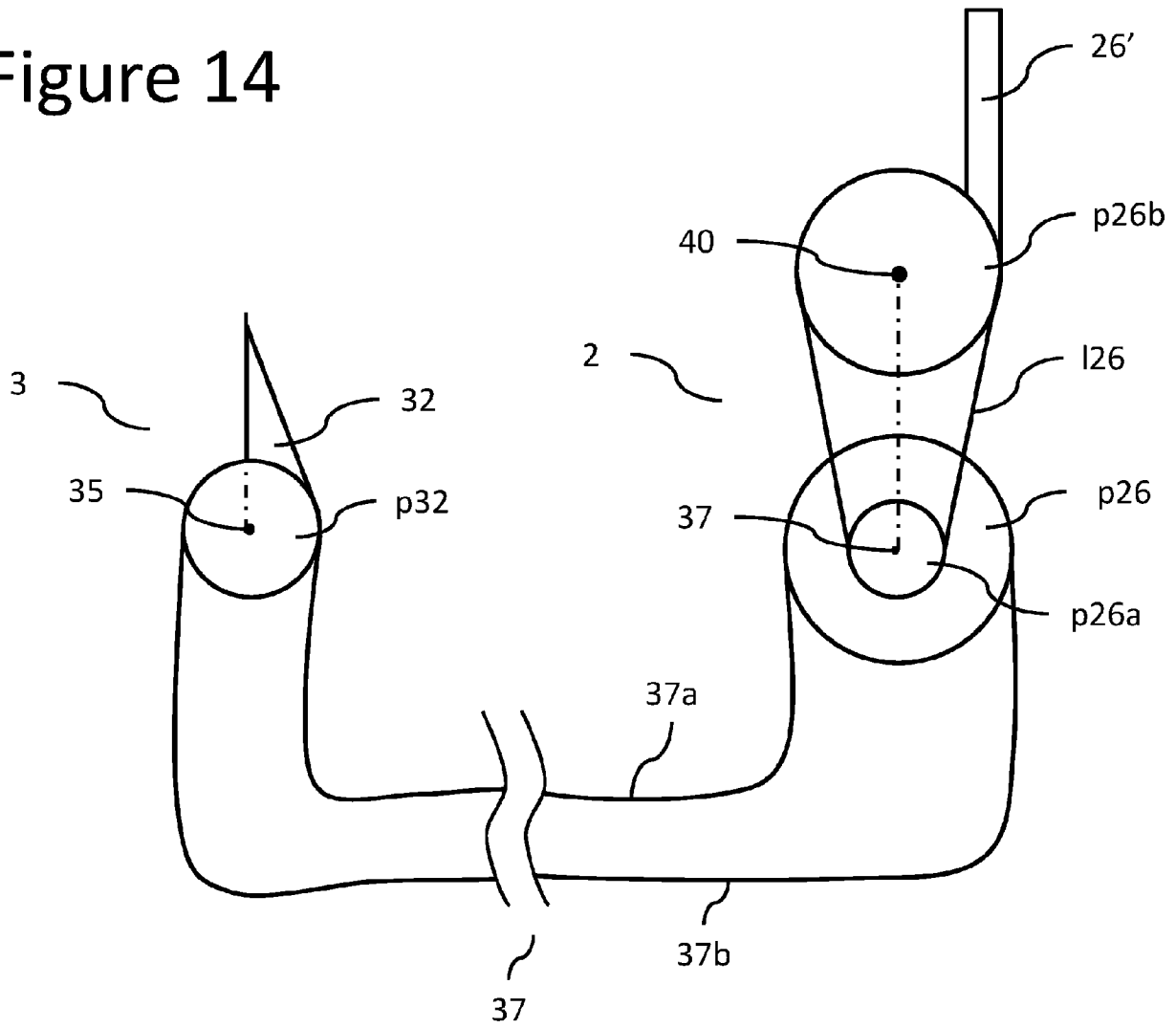


Figure 15

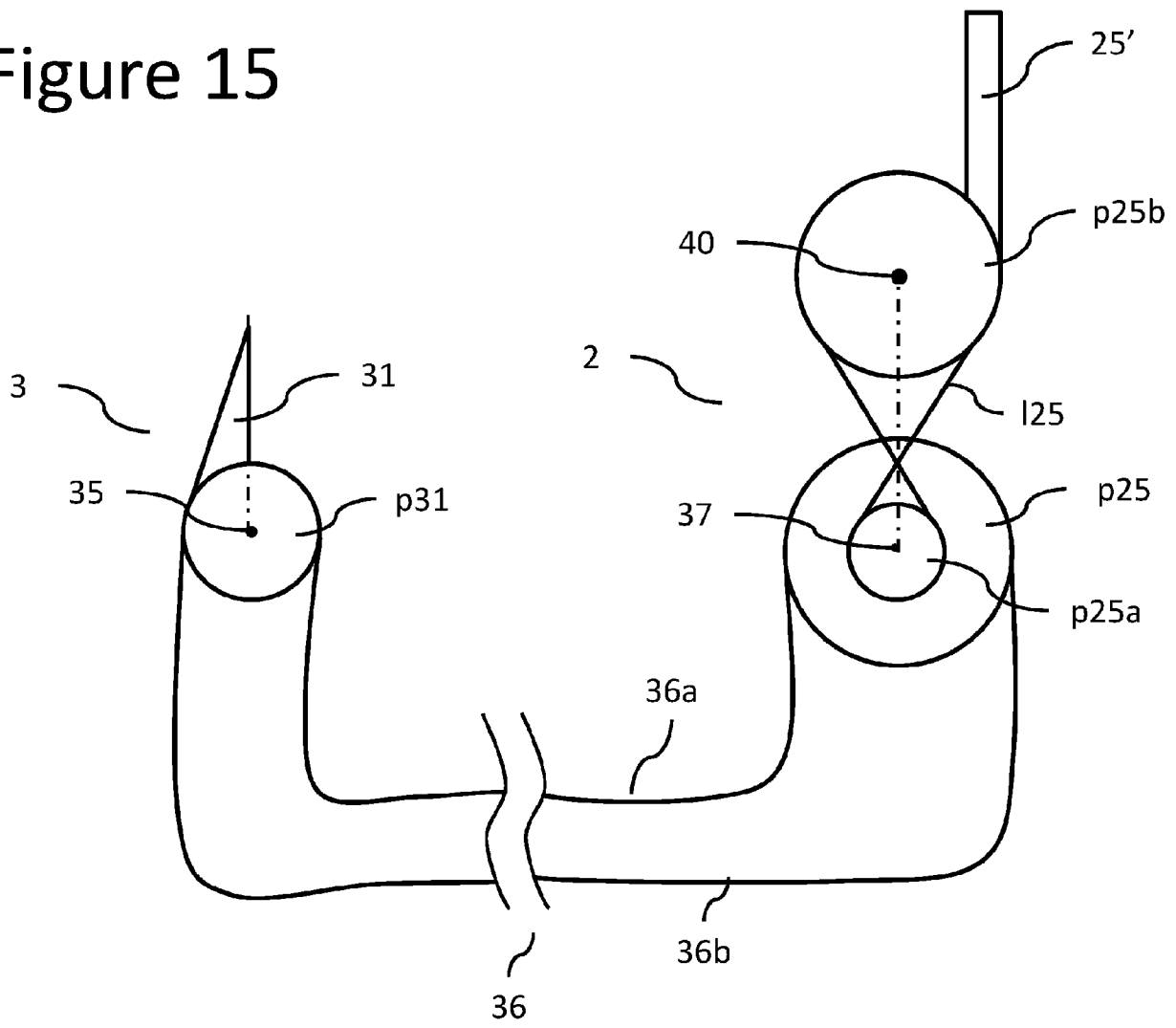


Figure 16

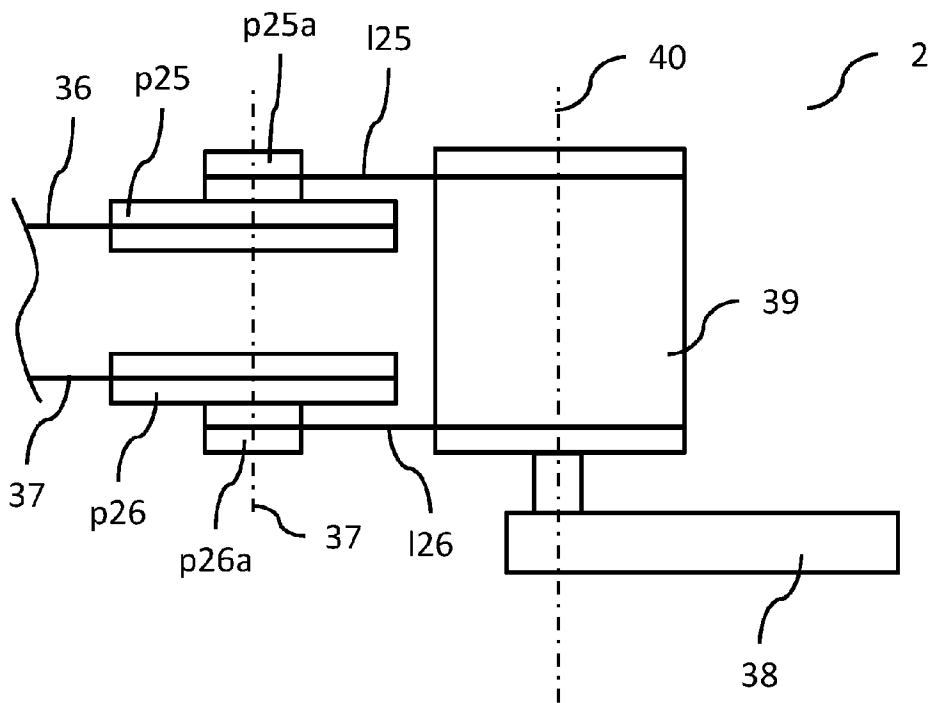


Figure 17

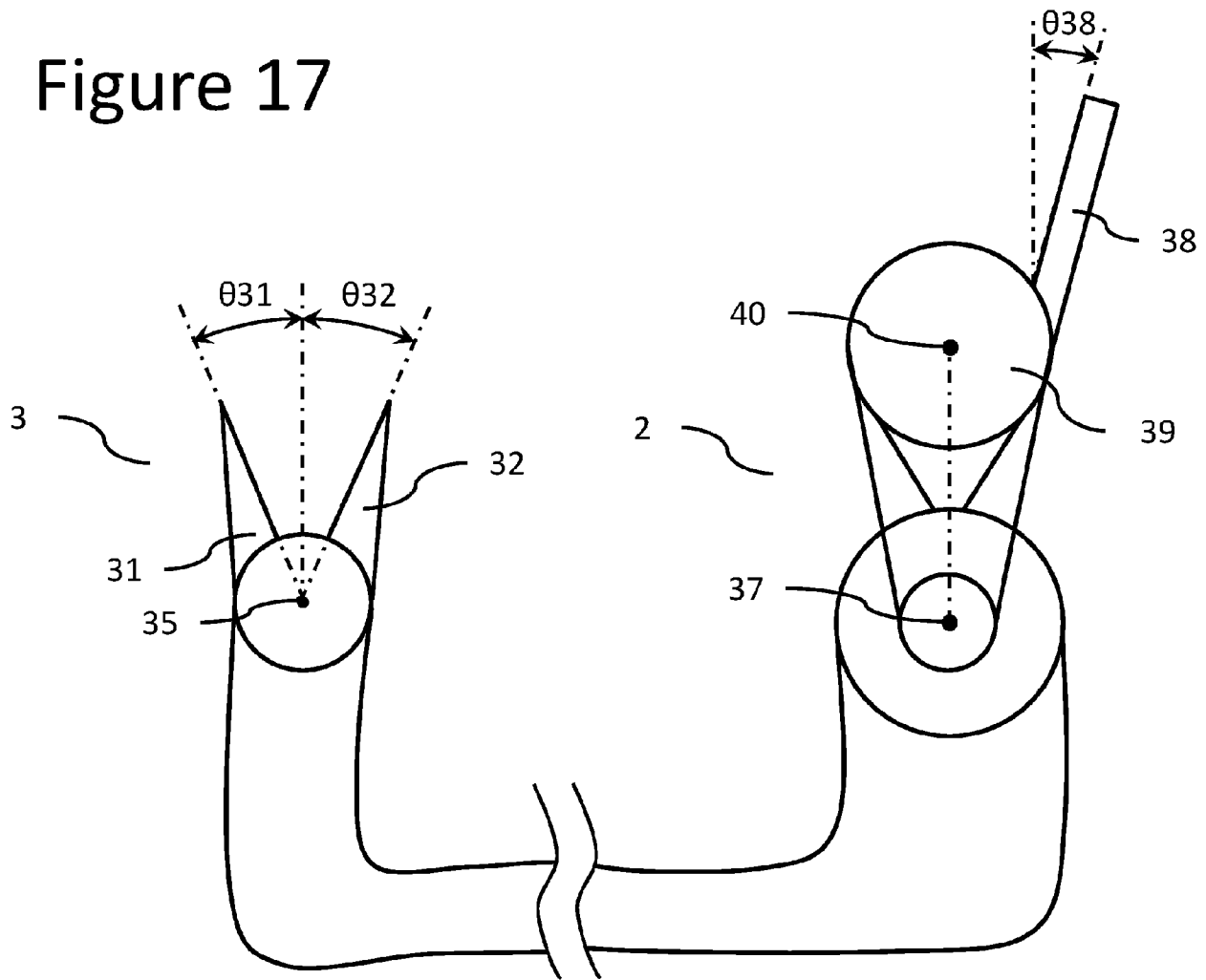


Figure 18

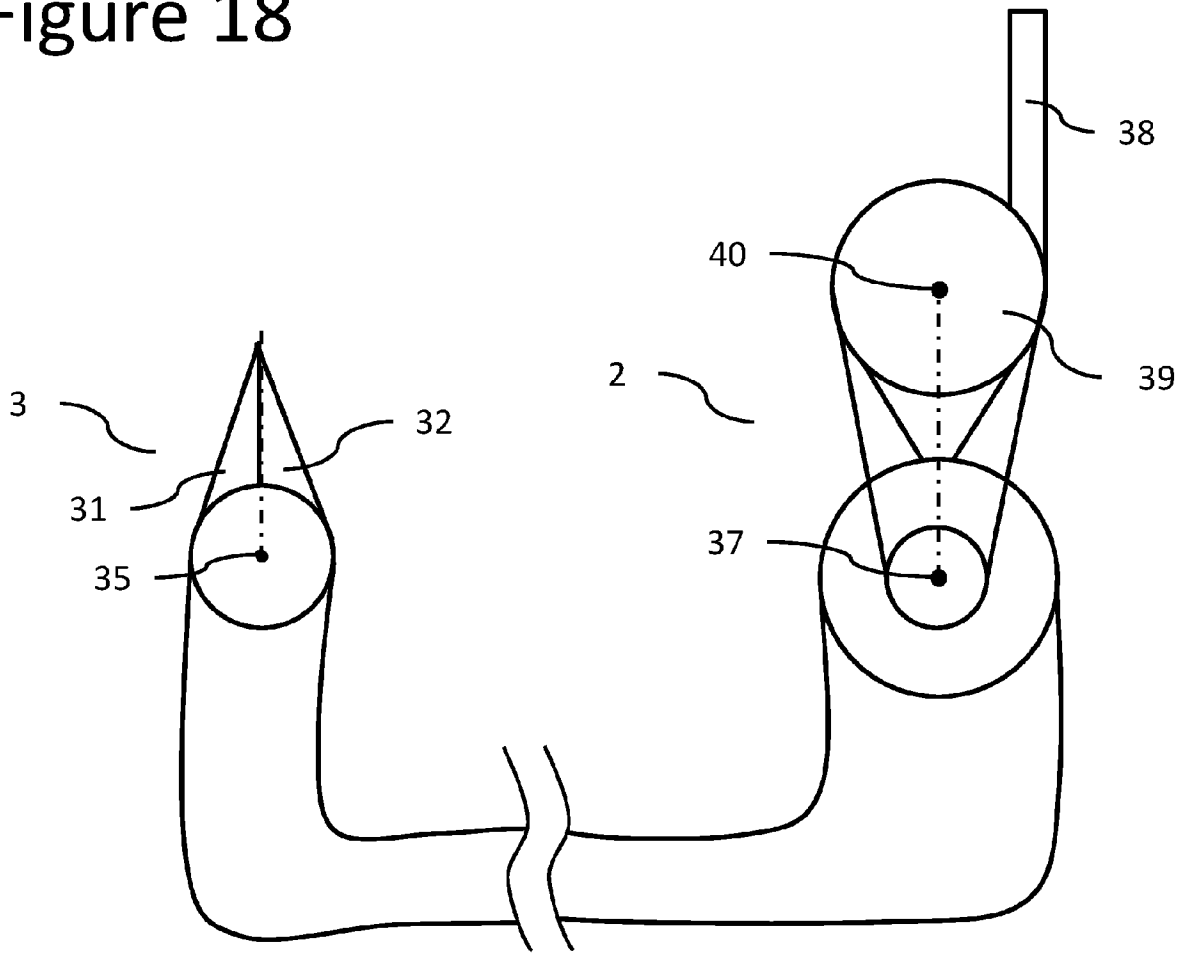


Figure 19

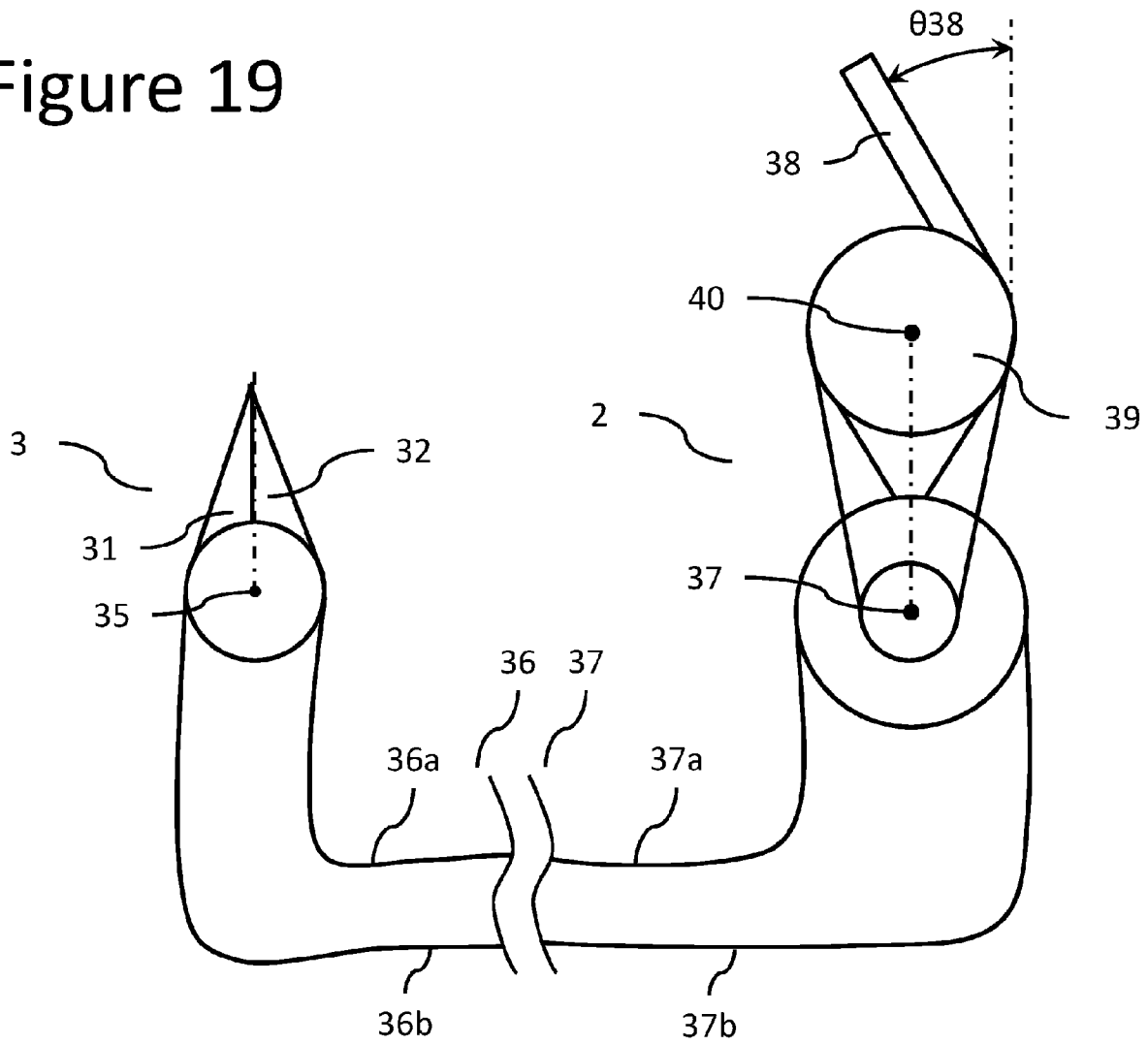


Figure 20

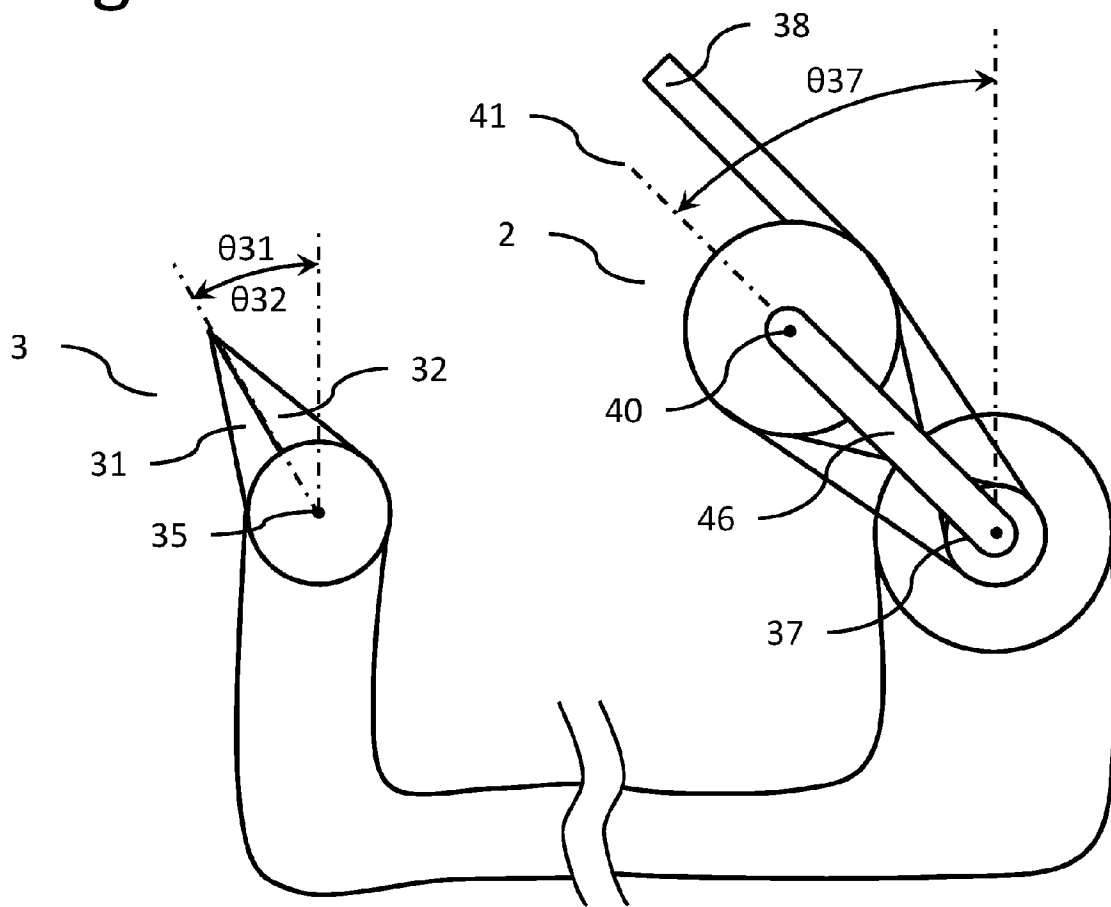


Figure 21

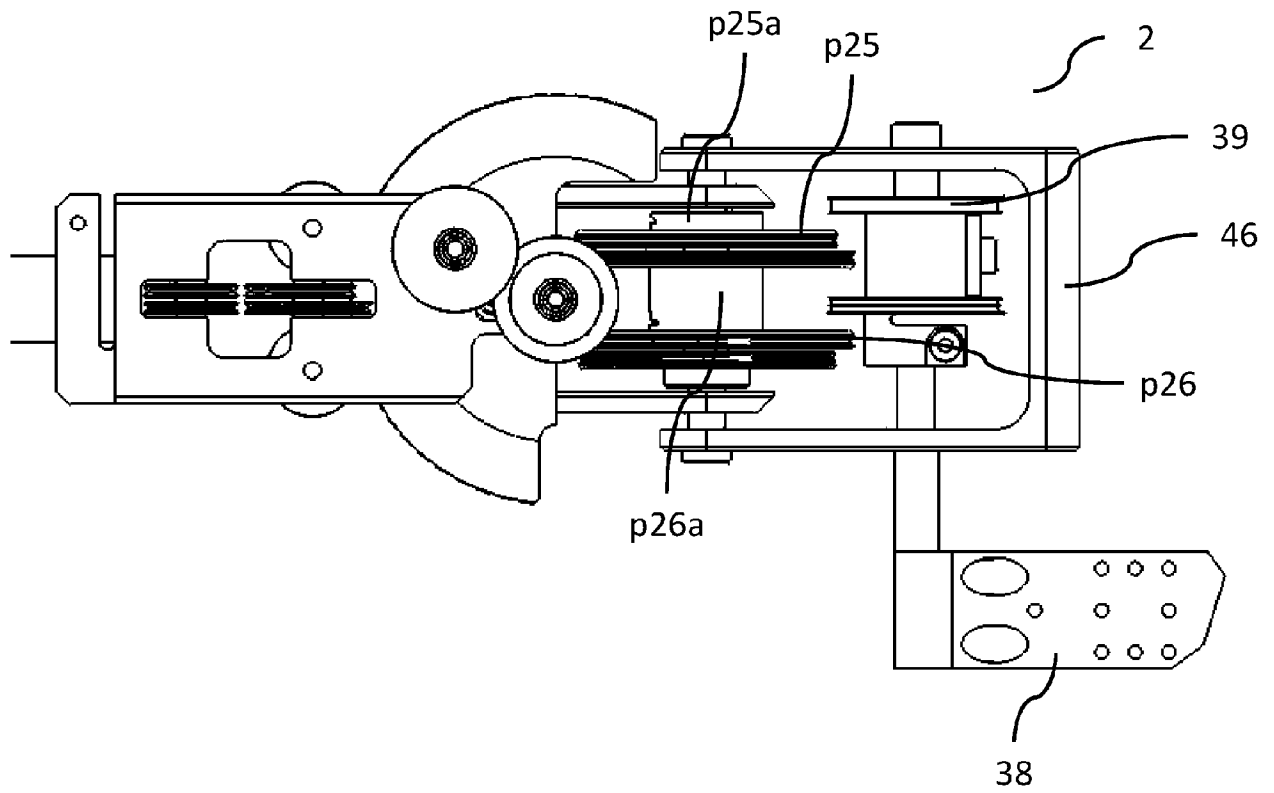


Figure 22

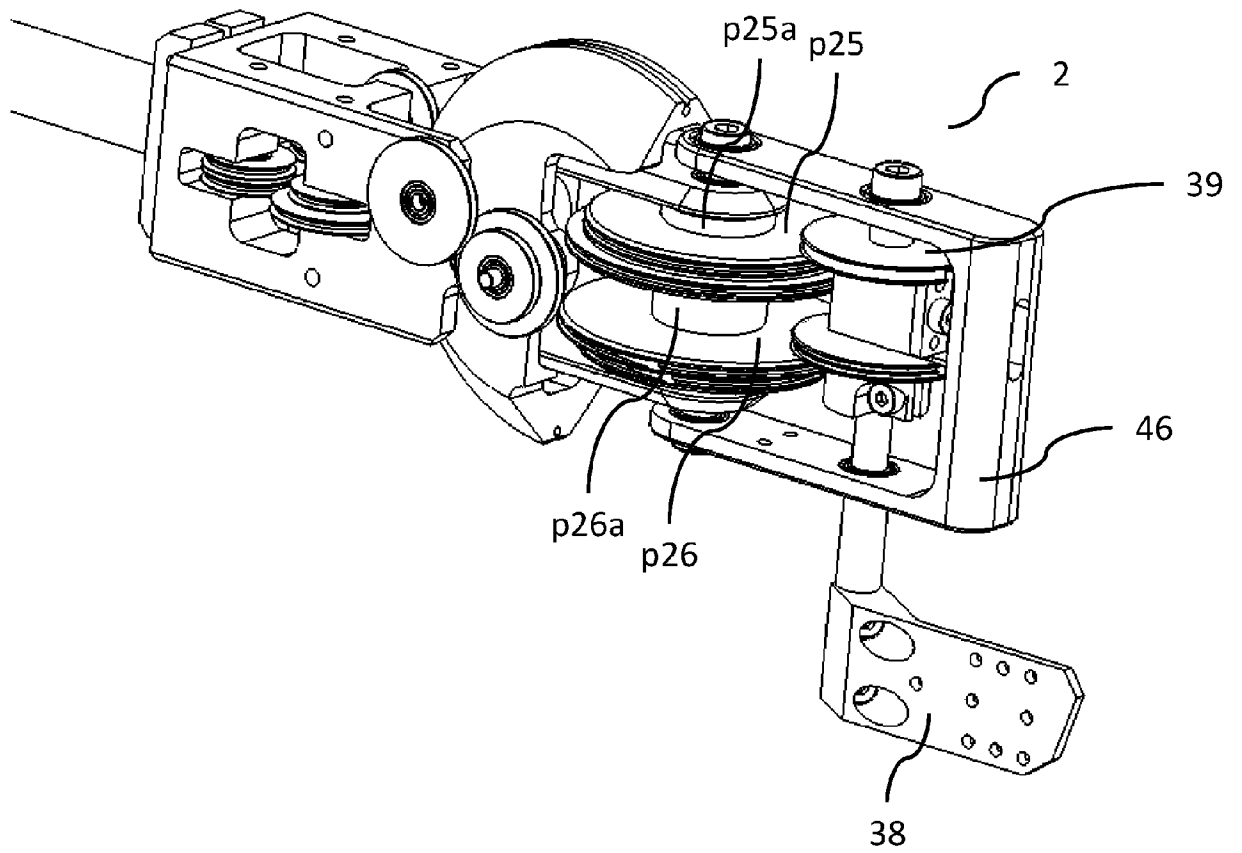


Figure 23

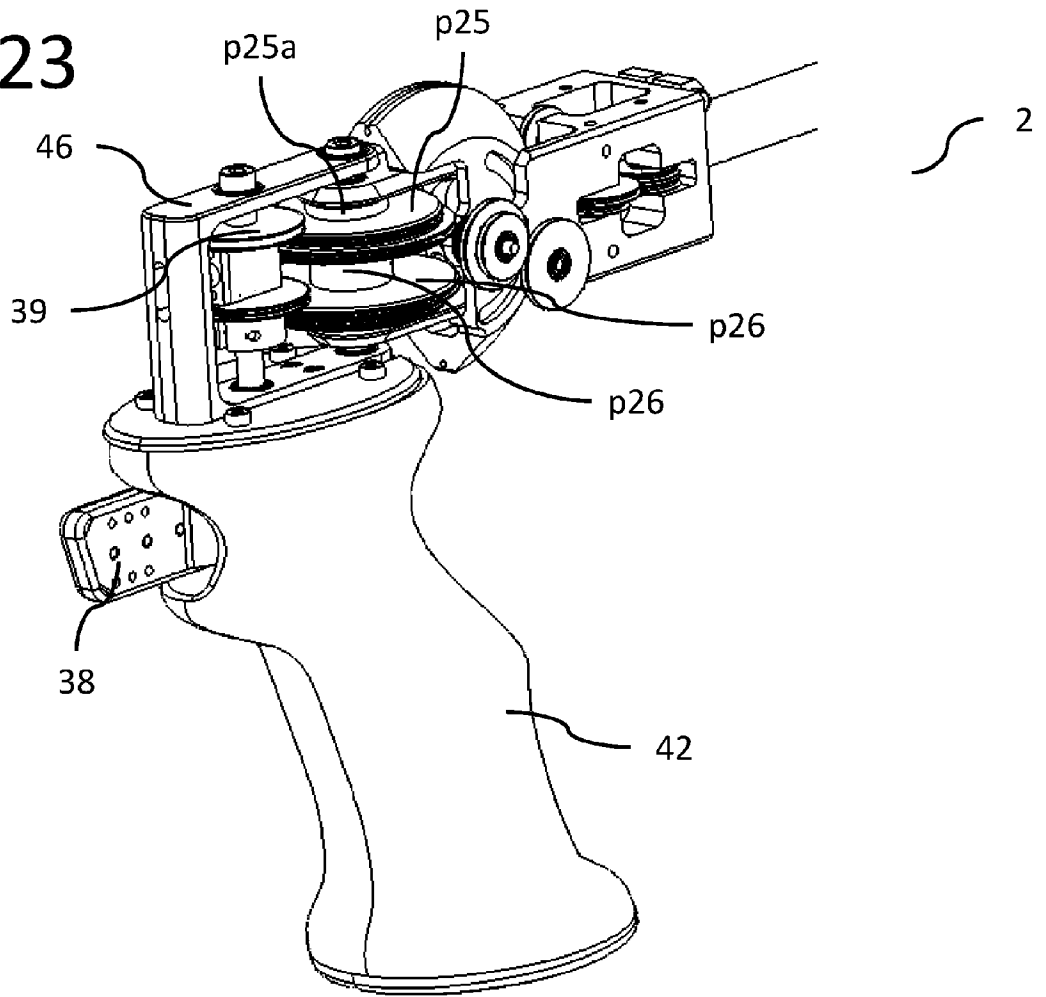


Figure 24

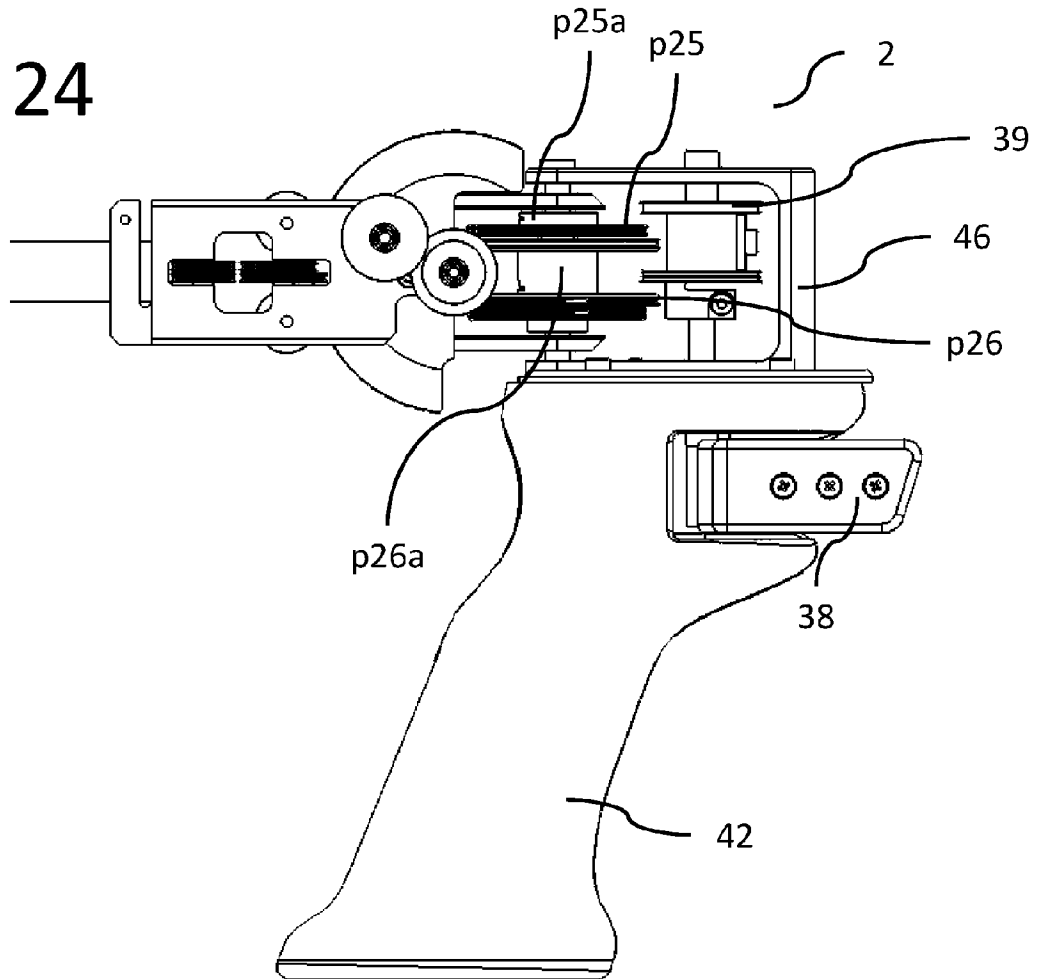


Figure 25

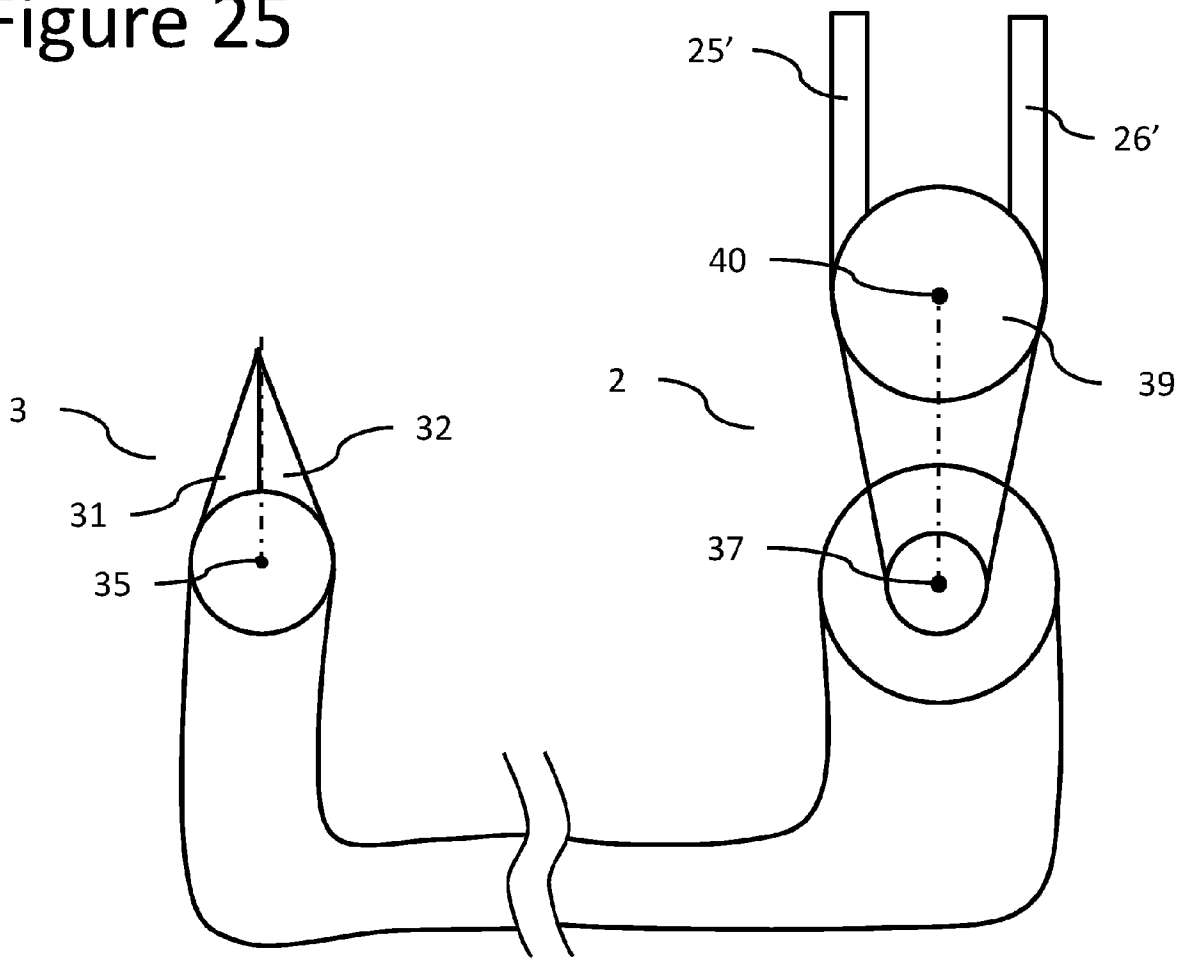


Figure 26

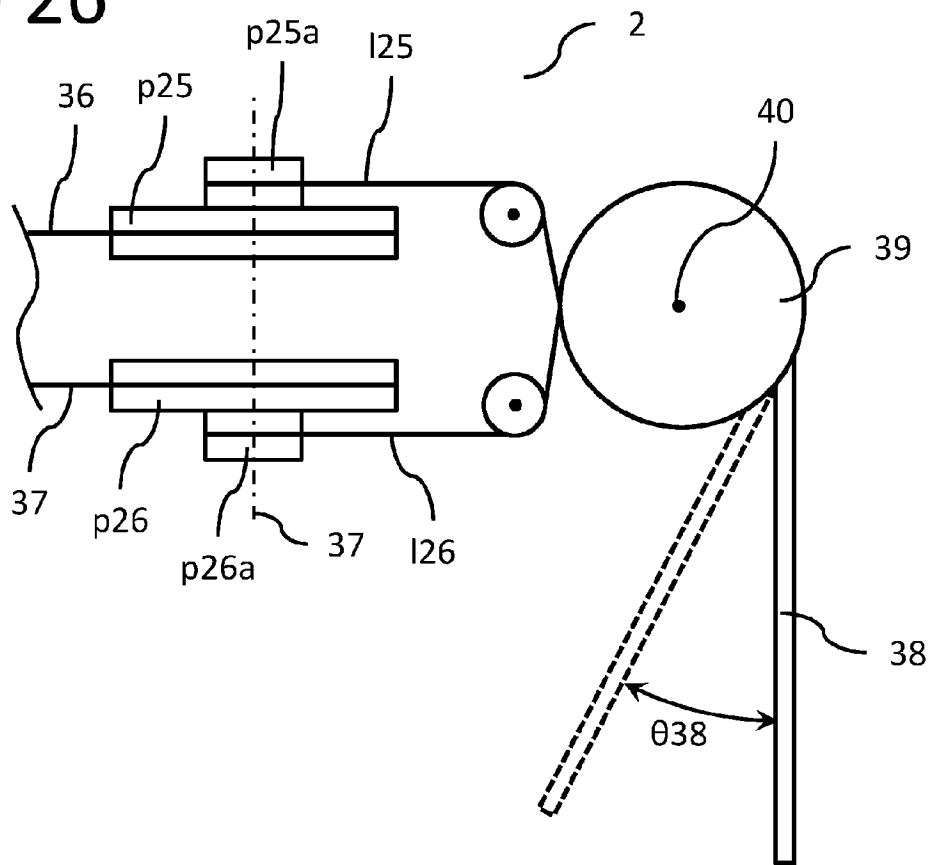


Figure 27

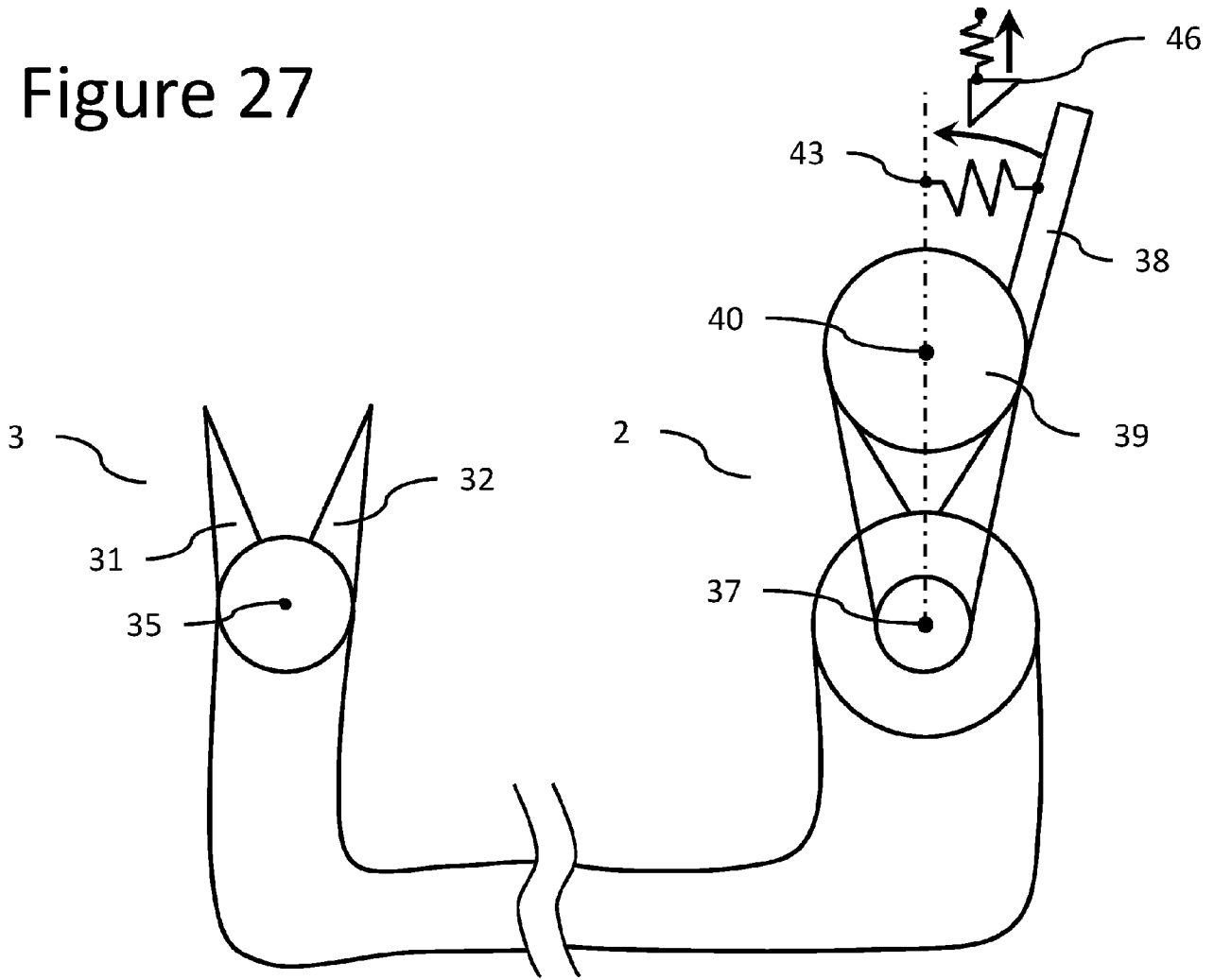


Figure 28

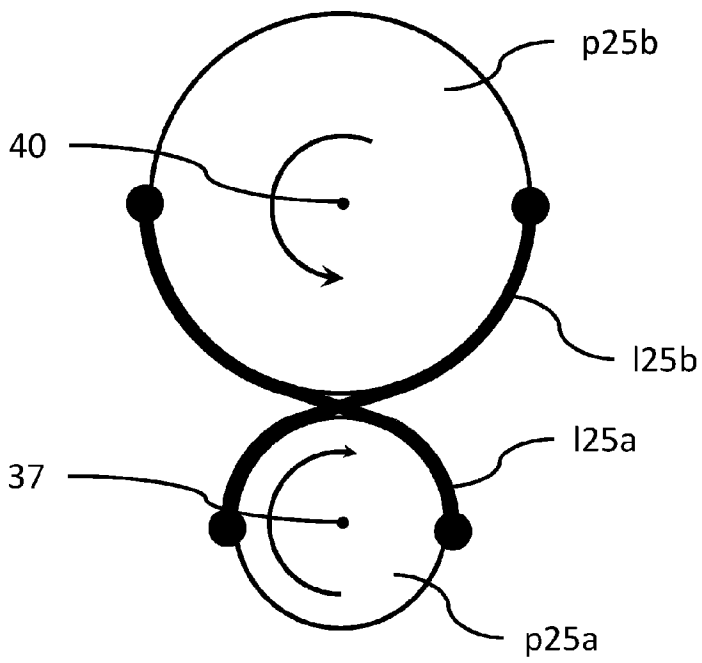


Figure 29

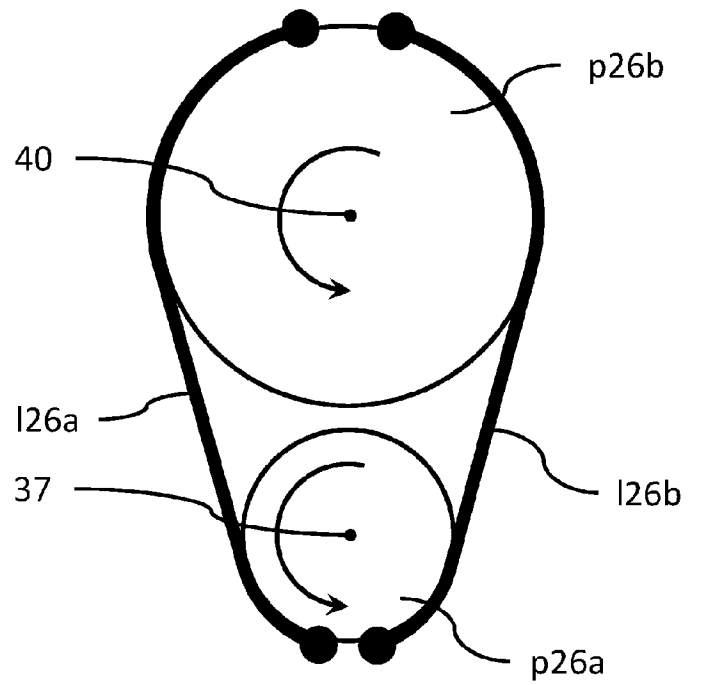


Figure 30

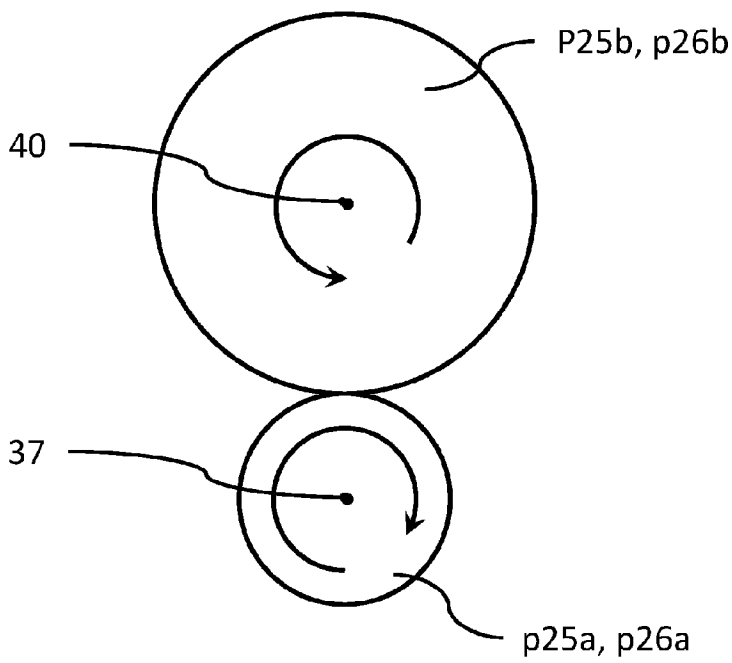


Figure 31

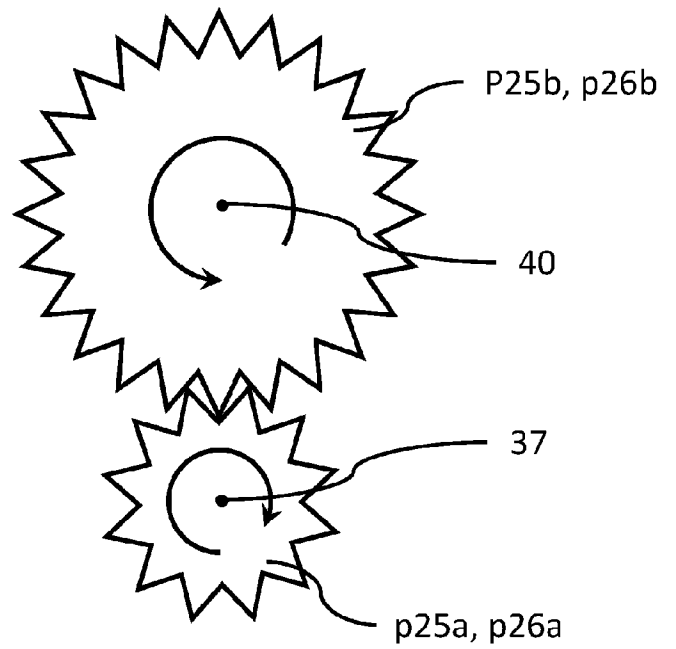


Figure 32

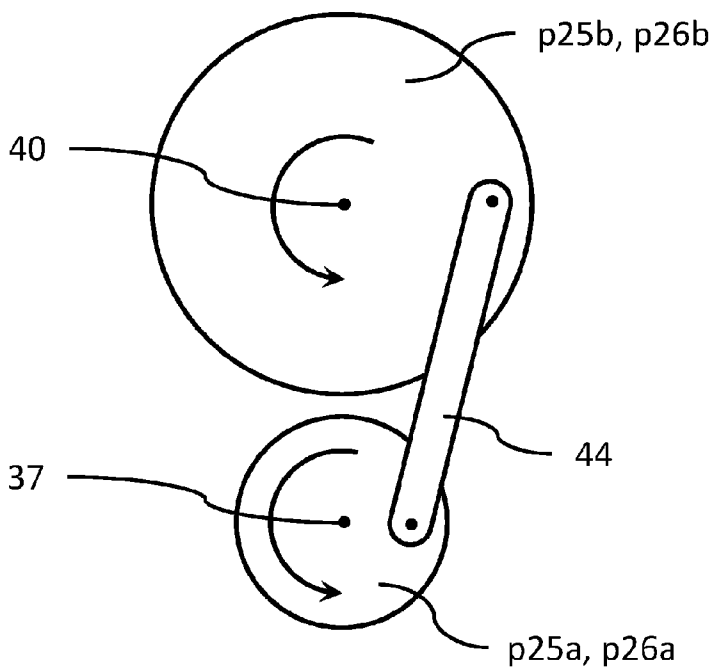


Figure 33

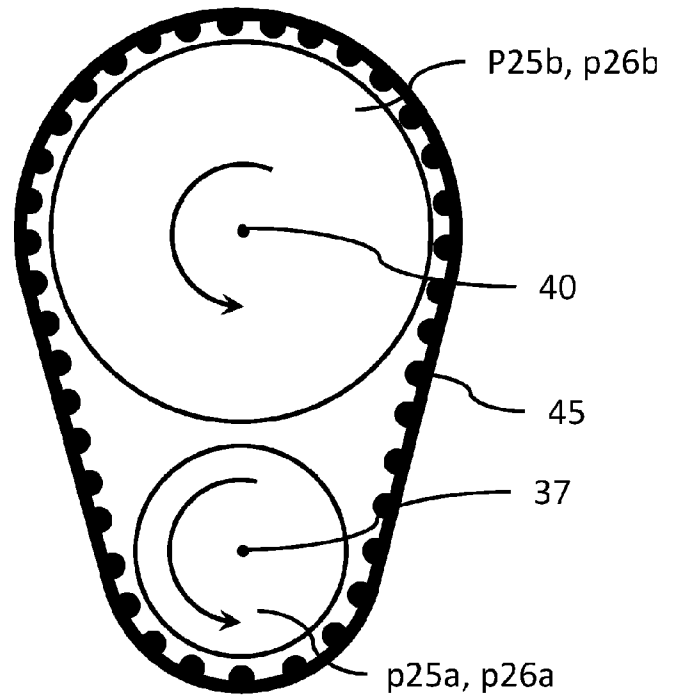


Figure 34

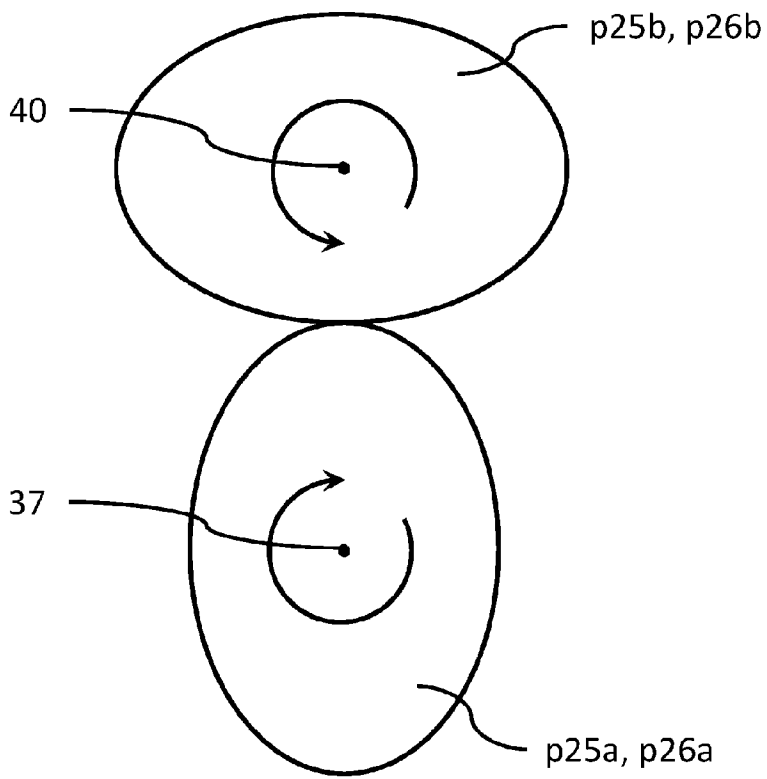


Figure 35

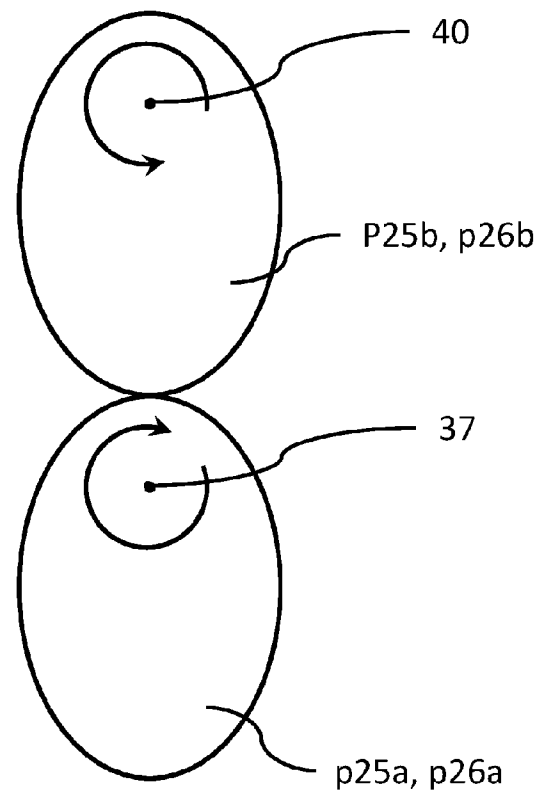


Figure 36

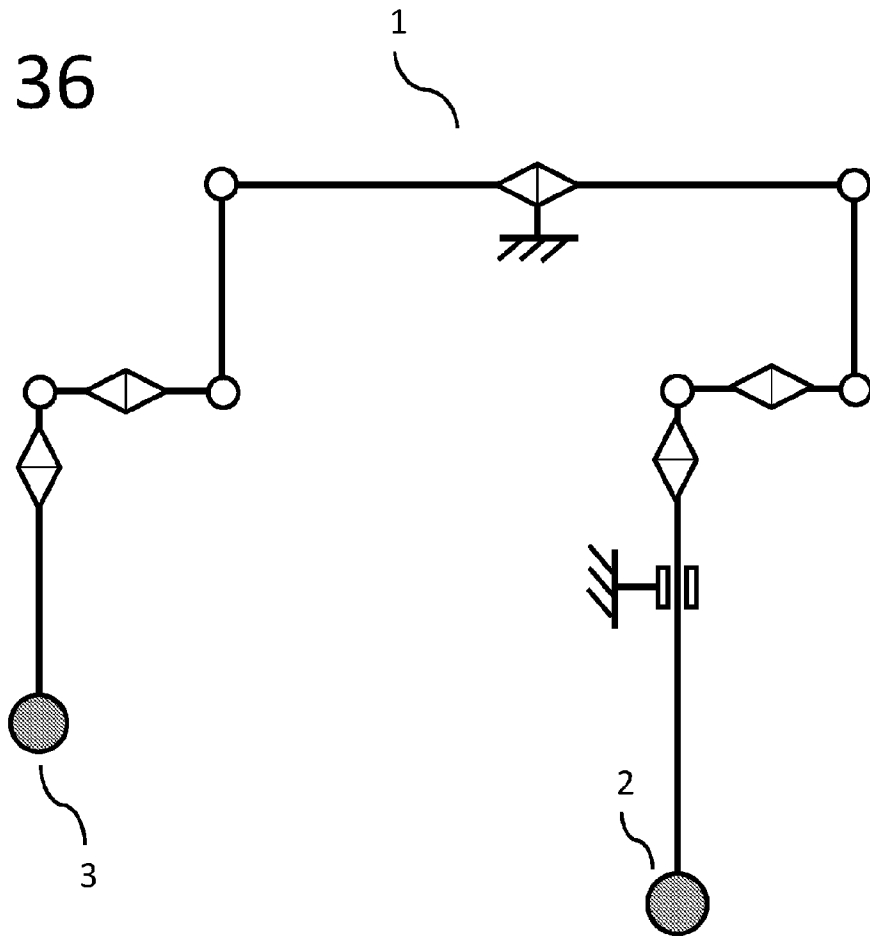


Figure 37

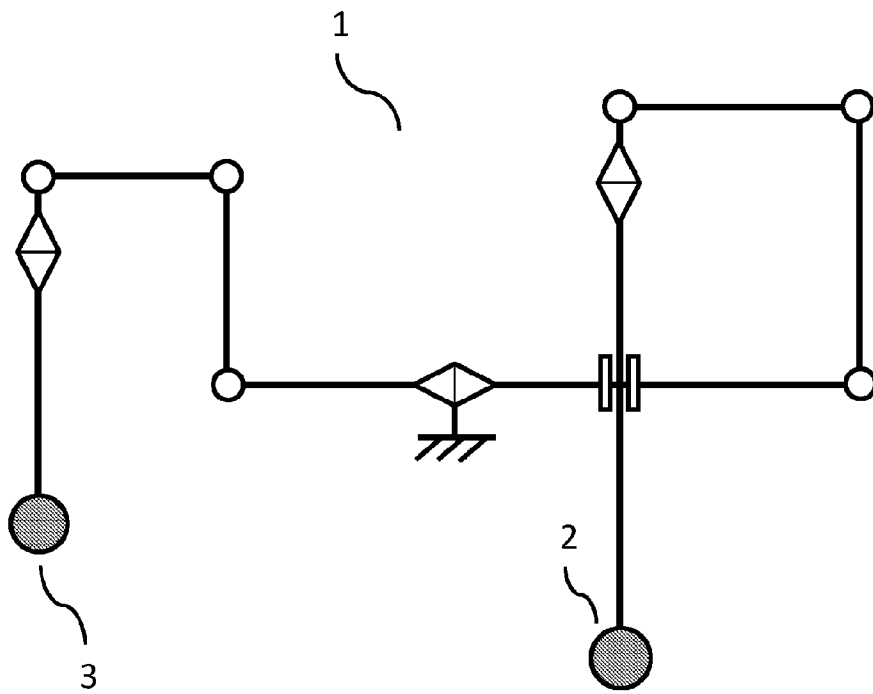


Figure 38

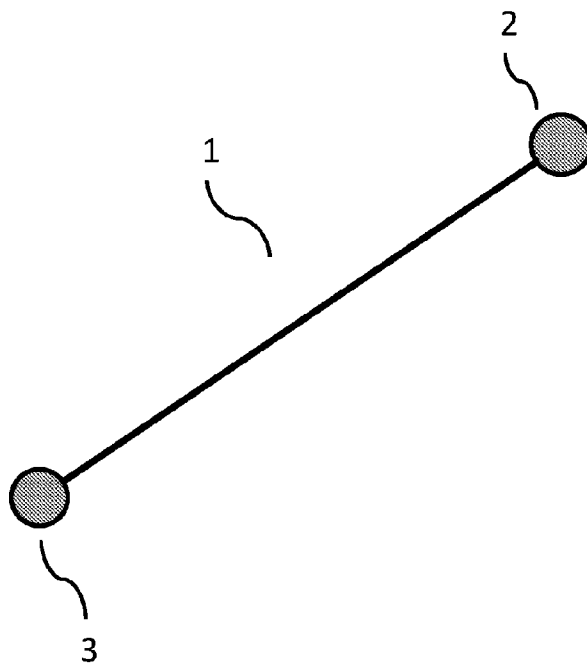


Figure 39

