



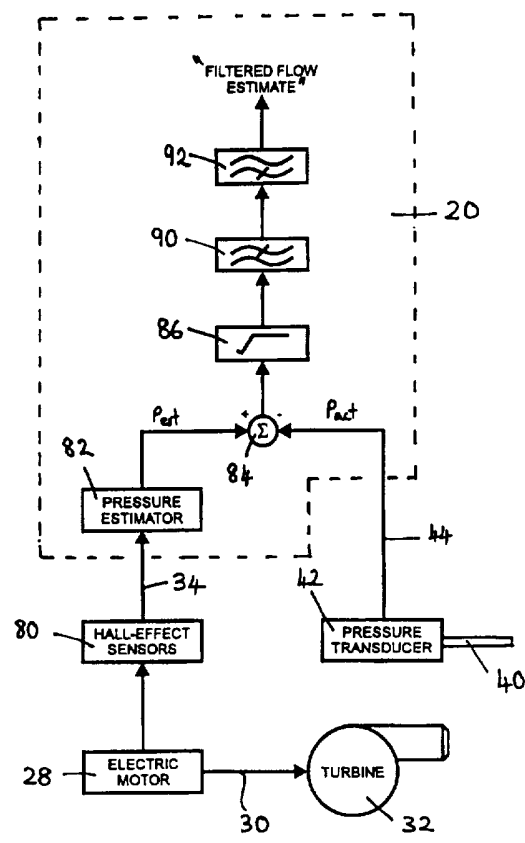
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<p>(21) International Application Number: PCT/AU96/00580 (22) International Filing Date: 13 September 1996 (13.09.96) (30) Priority Data: PN 5478 15 September 1995 (15.09.95) AU (71) Applicant (for all designated States except US): RESMED LIMITED [AU/AU]; 82 Waterloo Road, North Ryde, NSW 2113 (AU). (72) Inventors; and (75) Inventors/Applicants (for US only): FARRUGIA, Steven, Paul [AU/AU]; 10 Bruce Street, Bexley, NSW 2207 (AU). FINN, Shane, Darren [AU/AU]; 4 Sophia Crescent, North Rocks, NSW 2151 (AU). (74) Agent: SPRUSON & FERGUSON; G.P.O. Box 3898, Sydney, NSW 2001 (AU).</p>		<p>(81) Designated States: AL, AM, AT, AU, AZ, BA, BB, BG, BR, BY, CA, CH, CN, CU, CZ, DE, DK, EE, ES, FI, GB, GE, HU, IL, IS, JP, KE, KG, KP, KR, KZ, LC, LK, LR, LS, LT, LU, LV, MD, MG, MK, MN, MW, MX, NO, NZ, PL, PT, RO, RU, SD, SE, SG, SI, SK, TJ, TM, TR, TT, UA, UG, US, UZ, VN, ARIPO patent (KE, LS, MW, SD, SZ, UG), Eurasian patent (AM, AZ, BY, KG, KZ, MD, RU, TJ, TM), European patent (AT, BE, CH, DE, DK, ES, FI, FR, GB, GR, IE, IT, LU, MC, NL, PT, SE), OAPI patent (BF, BJ, CF, CG, CI, CM, GA, GN, ML, MR, NE, SN, TD, TG).</p> <p>Published With international search report.</p>

(54) Title: FLOW ESTIMATION AND COMPENSATION OF FLOW-INDUCED PRESSURE SWINGS IN CPAP TREATMENT AND ASSISTED RESPIRATION

(57) Abstract

A method of flow estimation during CPAP treatment is disclosed and involves measuring turbine (32) speed by means of the motor's Hall-effect sensors (80). The equivalent pressure, p_{est} , that would be developed by the turbine (32) for that measured speed if the flow were zero is estimated using a predetermined mathematical function. Coincidentally with the speed measurement and pressure estimation, the delivery tube pressure, p_{act} , is measured by the pressure transducer (42), and from p_{act} together with p_{est} , the difference between the two pressures is calculated, representing an estimation of flow, f_{est} . The flow estimation value can be linearised by the square root device (86), and then filtered by the combination of low pass and high pass filters (90, 92) to derive a filtered flow estimate value, that has the non-respiratory components removed. A method of flow compensation of flow-induced pressure swings also is disclosed.



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Flow Estimation and Compensation of Flow-Induced Pressure Swings in CPAP Treatment and Assisted Respiration

Field of the Invention

5 This invention relates to methods and apparatus for the estimation of respiratory flow, and to the compensation of pressure swings at the entrance of a patient's airway induced by respiratory flow in the course of continuous positive airway pressure (CPAP) treatment or assisted respiration.

10 Background of the Invention

 The administration of CPAP is common in the treatment of Obstructive Sleep Apnea (OSA) syndrome and Upper Airway Resistance syndrome. CPAP treatment effectively acts as a pneumatic splint of a patient's upper airway by providing air or breathable gas at a pressure elevated above atmospheric pressure to the entrance of the patient's airway. Treatment pressures in the range 4 - 20 cm H₂O are commonly
15 encountered. More sophisticated forms of CPAP include bi-level CPAP in which different treatment pressures are applied in synchronism with the inspiratory and expiratory phases of respiration, and autosetting (controlled variable treatment pressure) CPAP, as described in U.S. Patent No. 5,245,995. In all forms of CPAP treatment it
20 is desired to maintain the treatment pressure, usually clinically determined by a physician, to be as constant as possible to maintain treatment efficacy without causing the patient undue discomfort by having to work against an unnecessarily high positive airway pressure.

 Common to all forms of CPAP apparatus is a mask worn by a patient having
25 connection via a flexible air delivery tube to a flow generator. The flow generator has a turbine driven by an electric motor that is under the control of a microprocessor-based controller.

 In this specification a reference to a "mask" is to be understood as including a nose mask, a mouth mask, a nose and mouth mask in combination or a full face mask.

Simple CPAP machines estimate the mask pressure from the motor speed and operate under speed regulation. More sophisticated machines incorporate a pneumatic pressure transducer that provides a feedback signal representative of pressure at either the mask or a point within the flow generator itself. If the pressure feedback signal is from the mask, additional tubing or wires must extend between the mask and the flow generator which can give rise to sterilisation and/or safety problems. If pressure feedback is from a point within the flow generator, or at some other point removed from the mask, the impedance of the air delivery tube can result in flow-induced pressure swings at the mask. The pressure swings can be up to $\pm 5\%$ of treatment pressure, and since it is desired to provide the patient with the minimum treatment pressure to provide treatment efficacy and yet avoid the patient doing unnecessary work during exhalation, these pressure swings are undesirable and should be eliminated as far as possible.

It is also desirable to be able to accurately determine dynamic air flow in the delivery tube and mask. "Flow" is to be understood as including both ventilation volume and a volumetric flow rate. The flow will have a component due to the flow generator that is modulated by patient respiration. The measurement of air flow in the air delivery tube can beneficially be used to measure the average volume breathed by the patient and to determine whether the patient is inhaling (inspiring) or exhaling (expiring), the latter of which is crucial in the implementation of bi-level CPAP. Currently this is done using an in-line sensor to directly measure flow, or by measuring the pressure drop across a restriction in the air delivery tube (or alternatively, the pressure drop along the air delivery tube). These methods require the use of additional transducers, and in some cases additional wiring or tubing to connect the transducer to an appropriate point in the control circuitry of the CPAP apparatus.

It thus also is desirable to accurately measure or estimate air flow from the stand-point of enabling advanced control over the administration of CPAP treatment

and ensuring efficacy of treatment and patient compliance without reducing patient comfort.

The present invention is directed to overcoming or at least ameliorating one or more of the foregoing problems.

5

Summary of the Invention

In one broad form, the invention discloses a method to estimate gas flow from a turbine, the method comprising the steps of:

- 10 measuring the pressure of the gas flowing from the turbine when operating at a known rotational speed;
- estimating the pressure of gas that would be delivered by said turbine at the known rotational speed if there was no flow; and
- calculating the difference between the measured pressure and the estimated pressure to estimate the gas flow.

- 15 In another broad form, the invention discloses a method to estimate the flow of breathable gas to a patient from a flow generator having a turbine in the administration of continuous positive airway pressure (CPAP) treatment or assisted respiration, the method comprising the steps of:

- measuring the pressure of gas (p_{act}) from the flow generator;
- 20 measuring the rotational speed (ω) of the turbine;
- estimating the pressure of gas (p_{est}) that would be delivered by the flow generator at the measured rotational speed if there were no flow to the patient; and
- calculating the difference between p_{est} and p_{act} to give the estimate of flow (f_{est}).

- 25 The said difference further can be signal-processed to give a direct estimate of flow. The processing can include filtering to give a direct estimate of flow.

The invention yet further discloses a method to reduce flow-induced pressure swings at a patient mask during the administration of CPAP treatment or assisted

respiration, said mask being coupled to a flow generator by a gas delivery tube and the pressure of delivered gas being measured at a point remote from said mask, said measured pressure being used to derive a treatment pressure control signal supplied to said flow generator to control said desired treatment pressure, the method comprising
5 the steps of:

determining the flow of gas to the patient;

scaling said determined flow; and

adjusting said treatment pressure control signal by said scaled flow.

The scaled flow can be further filtered to pass only the scaled flow
10 corresponding to increases in flow, corresponding to a reduction in the desired treatment pressure.

The invention yet further discloses apparatus to estimate the flow of gas from a flow generator turbine supplying breathable gas in CPAP treatment or assisted respiration, the apparatus comprising:

15 pressure measurement means for measuring the pressure of gas from the turbine when operating at a known rotational speed;

pressure estimation means for estimating the pressure of gas that would be delivered by said turbine at the known rotation speed if there was no flow; and

processor means for calculating the difference between the measured pressure
20 and the estimated pressure to give an estimation of flow.

The invention yet further discloses apparatus to provide CPAP treatment or assisted respiration for supplying a positive treatment pressure of breathable gas at the entrance of a patient's airway, the apparatus comprising:

a flow generator having a turbine;

25 a gas delivery tube connected at one end thereof with the flow generator;

a patient mask connected to the other end of the delivery tube to be worn by the patient;

pressure sensor means sensing delivery pressure from either the flow generator or the delivery tube remote from the mask; and

processor means for controlling the flow generator, and further operable to estimate the flow of breathable gas by estimating the pressure of gas that would be delivered by the flow generator at the actual turbine rotational speed for zero flow and calculating the difference between the measured pressure and said estimated pressure to give an estimate of flow.

The apparatus can be further operable to scale the flow and compensate said pressure control signal by the scaled flow. The said difference further can be signal processed to give a direct estimate of flow. The processing can include filtering to remove non-respiratory components.

Brief Description of the Drawings

- Fig. 1 is a schematic block diagram of CPAP treatment apparatus;
- Fig. 2 is a cross-sectional view of the air delivery tube at the point where pressure is sensed;
- Fig. 3 is a block flow diagram describing the estimation of flow;
- Fig. 4 is a schematic block diagram relating to Fig. 3; and
- Fig. 5 is a schematic block diagram relating to the compensation of flow-induced pressure swings; and
- Fig. 6 is a chart of pressure swing versus set-point (treatment) pressure.

Detailed Description of Preferred Embodiments and Best Mode

The embodiments described relate to CPAP treatment apparatus, however it is to be understood that the invention equally has application in apparatus for the provision of assisted respiration or ventilation.

Flow Estimation

As shown in Fig. 1, the CPAP flow generator 10 is coupled to an air (or breathable gas) delivery tube 12, in turn coupled with a nose mask 14 being worn by a patient 16. The flow generator 10 comprises a microprocessor-based motor controller 20 that in one preferred form can include a 8-bit micro-controller such as the
5 Motorola™ MC68HC805B6. The motor controller 20 is connected with an electric motor power supply 24 by a control line 22. The power supply 24 provides a supply of electrical energy, in the preferred form being DC, to the electrical motor 28 by a supply line 26. The electrical motor 28 is connected with a turbine 32 by a mechanical
10 coupling 30. The electric motor 28 also is connected to the motor controller 20 by a signal line 34.

The turbine 32 provides breathable gas (including air) to the delivery tube 12 at a pressure elevated above atmospheric, and at a flow rate to satisfy a patient's treatment and respiration needs. This is achieved by speed control of the electric motor
15 28 and depended upon the pneumatic capacity of the turbine 32. The electric motor 28 preferably is a brushless DC type, such as the PAPST™ ECA 27-11. This motor has integral Hall-effect sensors that provide an electrical signal representative of motor speed provided to the motor controller 20 on the signal line 34. The electric motor 28 can alternatively have connected to it an optical or mechanical tachometer or any other
20 convenient rotational speed-sensing device. The speed of a DC motor is directly proportional to the armature voltage as provided by the motor power supply 24. There is a relationship between motor speed, turbine delivery pressure and flow that can be determined by experimentation.

In the bi-level form of CPAP, the separate inspiratory and expiratory treatment
25 pressures are achieved by rapid turbine speed control, although the use of solenoid-operated spill valves also is known in the art.

A pressure sensing tube 40 is connected with the air delivery tube 12 at a point proximate the exit of the turbine 32 within the casing of the flow generator 10. The

sensing tube 40 is connected with a pressure transducer 42 resulting in an electrical signal indicative of turbine delivery pressure being passed to the motor controller 20 on a signal line 44.

The flow generator 10, including the pressure sensing tube 40 and pressure transducer 42, is commercially available as the present applicant's Sullivan™ III CPAP machine.

The pressure sensing tube 40 can alternatively be ported into the delivery tube 12 at any point along the length of that tube, or be ported into the mask 14 itself. It further is possible for the pressure transducer 42 to be proximate the delivery tube 12 so that there is only a small length of tubing from a port into the delivery tube 12 to the transducer 42, with the signal line 44 thus extending out of the casing of the flow generator 10.

Fig. 2 shows, in cross-section, detail of the region of the delivery tube 12 to which the pressure sensing tube 40 connects. The pressure sensing tube 40 attaches a pressure sensing port 50 located downstream of an orifice plate 52. The orifice plate represents an impedance that introduces a local pressure disturbance resulting in an air recirculation region 54 and a laminar flow region 56 extending downstream from the orifice plate 52. The pressure sensing port 50 is located in the recirculation region 54. Such a pneumatic recirculation also can be achieved by a localised reduction in the diameter of the air delivery tube 12.

A method of flow estimation now will be described with reference to Figs. 3 and 4. As would be apparent to one skilled in the art, the processing to be described can readily be implemented by way of a computer program. In the first step 60, the motor speed is measured by means of the motor's Hall-effect sensors 80. From this rotational speed value, the equivalent pressure, p_{est} , that would be developed by the turbine 32 for that measured speed if the flow were zero is estimated in step 62 by means of the pressure estimator 82, using a predetermined mathematical function.

One method of estimating the equivalent pressure, p_{est} , is to apply the motor speed as the input to a quadratic function, having the form:

$$p_{est} = c_1\omega^2 + c_2\omega + c_3 \quad (1)$$

5 where c_1 , c_2 and c_3 are constants, which may take any value including zero, derived from previously determined pressure/speed characteristics of the turbine 32, and ω is the motor speed. On the basis of the applicant's Sullivan TM III machine as described, representative co-efficient values are $c_1 = 118$, $c_2 = 0$ and $c_3 = 0$. The coefficients
10 were calculated using a linear regression technique on the pressure/speed data for zero flow of the Sullivan TM III apparatus. The impedance of any inlet baffle and the pneumatic circuit of the turbine affect the coefficients.

In an alternative implementation, a higher order polynomial may be used to estimate the equivalent pressure, for zero flow, from motor speed, motor current and/or
15 armature voltage.

In another alternative implementation, a lookup table may be used to estimate the equivalent pressure for zero flow from motor speed, motor current and/or armature voltage based on an empirical set of measurements.

Coincidentally the speed measurement and pressure estimation with pressure
20 steps 60.62, the delivery tube pressure, p_{act} is measured in step 64 by means of the pressure transducer 42, and p_{act} together with p_{est} are passed to a differential summation device 84 whereby, in step 66, the difference between the two pressures is calculated. The output from the summation device 84 represents an estimation of flow,
 f_{est} .

25 A conventional orifice plate meter consists of a thin plate which is inserted into the air-delivery tube. The plate has a central orifice that is smaller than the diameter of the tube and ports either side of the plate for measuring pressure. The obstruction results in a constriction of the flow and a local pressure disturbance which can be

measured. The flow q is determined by measuring the pressure at the sensing ports and is given by

$$q = c\sqrt{p_1 - p_2} \quad (2)$$

5

where c is a constant for a given configuration, p_1 is the pressure at the sensing port preceding the orifice plate and p_2 is the pressure at the sensing port following the plate.

As previously noted, measurement of both pressure and flow in a CPAP machine usually requires at least two transducers. A pressure transducer is required for pressure regulation and a second transducer is required for flow measurement. The second transducer may be either a pressure transducer or a flow transducer. In the first case flow is given by equation (2), in the later case flow is measured directly.

10

For non-zero flow, it is seen from equation (2) that the pressure p_1 is greater than p_2 remains constant.

15

At zero flow, the pressures p_1 and p_2 are equal and can be estimated from a quadratic function of the motor speed having the form of equation (1).

For non-zero flow, p_1 is increased, to meet the increased flow, by increasing the motor speed. Therefore, the pressure estimate derived from the motor speed also increases. The change in motor speed is approximately proportional to the change in flow, then the change in p_{est} is proportional to the change in p_1 . The flow \hat{f}_{est} can be estimated, therefore, from the difference between the pressure estimate p_{est} and the measured pressure p_2 , ie.

20

$$\hat{f}_{est} = c\sqrt{p_{est} - p_2} \quad (3)$$

25

The orifice plate 52 has a 'square law' impedance, in which case the output of the summation device 84 represents "FLOW SQUARED". In such a case, the "FLOW SQUARED" value can be linearised in step 68 by the square root device 86. and then

filtered in step 70 by the combination of low pass and high pass filters 90.92 to derive a "FILTERED FLOW ESTIMATE" value, that has the non-respiratory components removed. The low pass filter preferably will have an upper frequency limit of 20Hz to remove noise, while the high pass filter preferably will have a lower frequency limit of
5 0.1Hz to remove non-respiratory components.

Flow Compensation

The performance of flow compensation, which enables flow induced pressure swings at the mask to be minimised, will now be described with reference to Fig. 5.

10 The method of flow compensation can be utilised using the flow estimation value calculated in accordance with the method described above, or on the basis of a flow measurement made by a flow transducer.

In a preferred embodiment, the flow-generator incorporates a pressure transducer used for pressure regulation such as shown in Fig. 1. The transducer 42
15 measures pressure in the gas delivery circuit at a point removed from the mask. The flow induced pressure perturbations at the mask are therefore larger than that at the controlled point. The compensation of flow-induced pressure perturbations at the mask is by way of compensating control over the mask pressure, while still retaining adequate flow for respiration purposes.

20 Fig. 5 shows the processing performed by the motor controller 20 in performance of the flow compensation. As would be apparent to one skilled in the art, the function of the logical blocks can be implemented by way of a computer program. Both the electric motor speed and the actual measured delivery pressure are provided to a computational element 100 respectively by the signal lines 34 and 44. The
25 computational element 100 estimates the flow in accordance with the technique described in conjunction with Figs. 3 and 4, thus the output of the computational element is the "FILTERED FLOW ESTIMATE". That signal is passed to a squarer element 102 to derive a signal representing "FLOW²". In the alternative, where the

orifice plate used to derive delivery pressure is a square-law type, then, as previously described, an estimate of "FLOW²" is obtained directly in the flow estimation method, hence the squaring function of the squarer element 102 need not be performed. The estimated "FLOW²" value is passed to a gain element 104 that scales the signal. The scale factor may take on any value, including one and zero, may have a positive or negative sign and may take on different values at different times. In a typical implementation, that incorporates an obstruction of the air-delivery circuit, the scale factor is zero for negative flow, ie when the mask pressure is less than the pressure at the turbine, and a small positive constant, less than one, when the flow is positive.

10 The scaled flow signal passes by a limiter element 106, the function of which is to limit the magnitude of the "FLOW COMPENSATION VALUE" to a predetermined value to ensure stability.

By way of further explanation, when pressure is measured from within the recirculation region 54, and is the controlled variable, the mask pressure initially increases with increasing flow and then falls. The deviation from the pressure set point can be reduced, therefore, by subtracting the scaled flow estimate from the pressure set point. However, if the estimated flow is negative (i.e. the measured pressure is greater than the estimate pressure), no compensation is implemented to avoid instability due to positive feedback.

20 As the mask pressure varies as the square of flow, the flow compensation technique can be refined by making the compensation value proportional to the *square* of flow. Beyond a certain flow value, the mask pressure will begin to fall with increasing flow. It may be desired, therefore, to limit the magnitude of the compensation value. The most preferable limit would be at the turning point of the pressure/flow curve. The turning point is variable and is a function of motor speed. Alternatively, and more simply, a fixed limit could be used.

25 The constants in equation (1) can be calculated from recorded pressure/speed data at zero flow. For the purposes of flow compensation, the value of the constant in

equation (3) may be unimportant (as it is replaced by a scaling factor), however, if required, it may be derived by fitting equation (3) to measured flow data. The complete flow compensation procedure is as follows:

- 5 1. calculate p_{est} from equation (1),
2. measure the pressure p_2 ,
3. calculate the compensation value ($p_{est}-p_2$), which is proportional to
flow squared,
4. if the compensation value is negative set the compensation to zero,
- 10 5. multiply the compensation value by the scale factor,
6. limit the magnitude of the compensation value, and
7. subtract the flow compensation from the pressure error.

The control loop minimises the difference between the set pressure and the
15 measured pressure, and at the same time minimises the difference between the pressure
that should be generated for the measured motor speed and the measured pressure.

The outputs from the limiter element 106 represents the "FLOW
COMPENSATION VALUE" scaled in accordance with the pressure-controlling
signals. The "PRESSURE SET POINT" is compared with the measured pressure at the
20 differential summation element 108, generating a "PRESSURE ERROR" signal. The
"PRESSURE ERROR" signal and the "FLOW COMPENSATION VALUE" form the
inputs to a further differential summation element 110, and in this way the control
variable of "TREATMENT PRESSURE ERROR" is compensated in accordance with
flow, the output from the summation element 110 passing to a controller unit 112 that
25 provides the controlling signal to the motor power supply 24 on the control line 22.

The set point pressure may not be the mask pressure, as is the case for the
arrangement shown in Fig. 1, where it is the turbine output pressure that is measured.
In that case, the pressure set point has been pre-compensated by the controller unit 112

to be in relation to the point where pressure actually is measured relative to the desired mask CPAP treatment pressure.

In tests of the flow compensation methodology described utilising the CPAP apparatus described above, for a set mask treatment pressure of 10 cm H₂O, the
5 magnitude of the pressure swings without compensation was 1.8 cm H₂O. With flow compensation in place, the swings are reduced to 0.7 cm H₂O. Over the range of 4 - 18 cm H₂O, the average reduction in the magnitude of the pressure swing at the mask reduced by respiratory flow was 64%. The data is shown in Fig. 6.

CLAIMS:

1. A method to estimate the flow of breathable gas to a patient from a flow generator having a turbine in the administration of continuous positive airway pressure (CPAP) treatment or assisted respiration, the method comprising the steps of:
5 measuring the pressure of gas (p_{act}) delivered by the flow generator;
measuring the rotational speed (ω) of the turbine;
estimating the pressure of gas (p_{est}) that would be delivered by the flow generator at the measured rotational speed if there were no flow to the patient; and
10 calculating the difference between p_{est} and p_{act} to give an estimate of the flow to the patient (f_{est}).

2. A method as claimed in claim 1, comprising the further step of taking the square root of the flow estimate to give a linearised flow estimate.
15

3. A method as claimed in claim 2, comprising the further step of filtering said linearised flow estimate to remove non-respiratory components.

4. A method as claimed in any one of claims 1, 2 or 3, whereby said step
20 of estimating comprises the step of performing the calculation:

$$p_{est} = c_1 \omega^2 + c_2 \omega + c_3$$

where c_1 , c_2 and c_3 are known constants.
25

5. A method as claimed in any one of claims 1, 2 or 3, whereby the step of estimating comprises the step of searching a look-up table tabulating incremental

rotational speeds with predetermined values of pressure for no flow to identify the relevant value of p_{est} .

6. Apparatus for estimating the flow of gas from a flow generator having
5 a turbine, and supplying breathable gas in the administration of CPAP treatment or assisted respiration, the apparatus comprising:

pressure measurement means for measuring the pressure of gas from the flow generator when operating at a known turbine rotational speed;

10 pressure estimation means for estimating the pressure of gas that would be delivered by said flow generator at the known rotation speed if there was no flow; and

processor means for calculating the difference between the measured pressure and the estimated pressure to give an estimation of flow.

7. Apparatus to provide CPAP treatment or assisted respiration by the
15 supply of a positive treatment pressure of breathable gas to a patient's airway, the apparatus comprising:

a flow generator having a turbine;

a gas delivery tube connected at one end thereof with the flow generator;

20 a patient mask to be worn by the patient connected to the other end of the delivery tube;

pressure sensor means sensing delivery pressure from either the flow generator or the delivery tube remote from the mask; and

25 processor means for controlling the flow generator, and further operable to estimate the flow of breathable gas to the patient by estimating the pressure of gas that would be delivered by the flow generator at the actual turbine rotational speed for zero flow and calculating the difference between the measured pressure and said estimated pressure to give said estimate of flow, said estimate of flow being utilised by the

processor to dynamically adjust a control signal provided to said flow generator to reduce flow-induced pressure swings at the mask.

8. A method to reduce flow-induced pressure swings at a patient mask during the administration of CPAP treatment or assisted respiration, said mask being coupled to a flow generator, having a turbine, by a gas delivery tube and the pressure of delivered gas being measured at a point remote from said mask, said measured pressure being used to derive a treatment pressure control signal supplied to said flow generator to control said desired treatment pressure, the method comprising the steps of:

determining the flow of gas to the patient;
scaling said determined flow; and
adjusting said treatment pressure control signal by said scaled flow.

9. A method as claimed in claim 8, comprising the further steps of filtering said scaled flow to pass only the scaled flow corresponding to increases in flow that correspond to a reduction in treatment pressure.

10. A method as claimed in claim 8 or claim 9, whereby said step of determining flow further comprises the steps of:

measuring the pressure of gas (p_{act}) delivered by the flow generator;
measuring the rotational speed (ω) of the turbine;
estimating the pressure of gas (p_{est}) that would be delivered by the flow generator at the measured rotational speed if there were no flow to the patient; and
calculating the difference between p_{est} and p_{act} to give the estimate of the flow to the patient (f_{est}).

11. A method as claimed in claim 10, whereby said step of estimating comprises the step of performing the calculation:

$$p_{\text{est}} = c_1 \omega^2 + c_2 \omega + c_3$$

5

where c_1 , c_2 and c_3 are known constants.

12. A method as claimed in claim 10, whereby the step of estimating comprises the step of searching a look-up table tabulating incremental rotational speeds
10 with predetermined values of pressure for no flow to identify the relevant value of p_{est} .

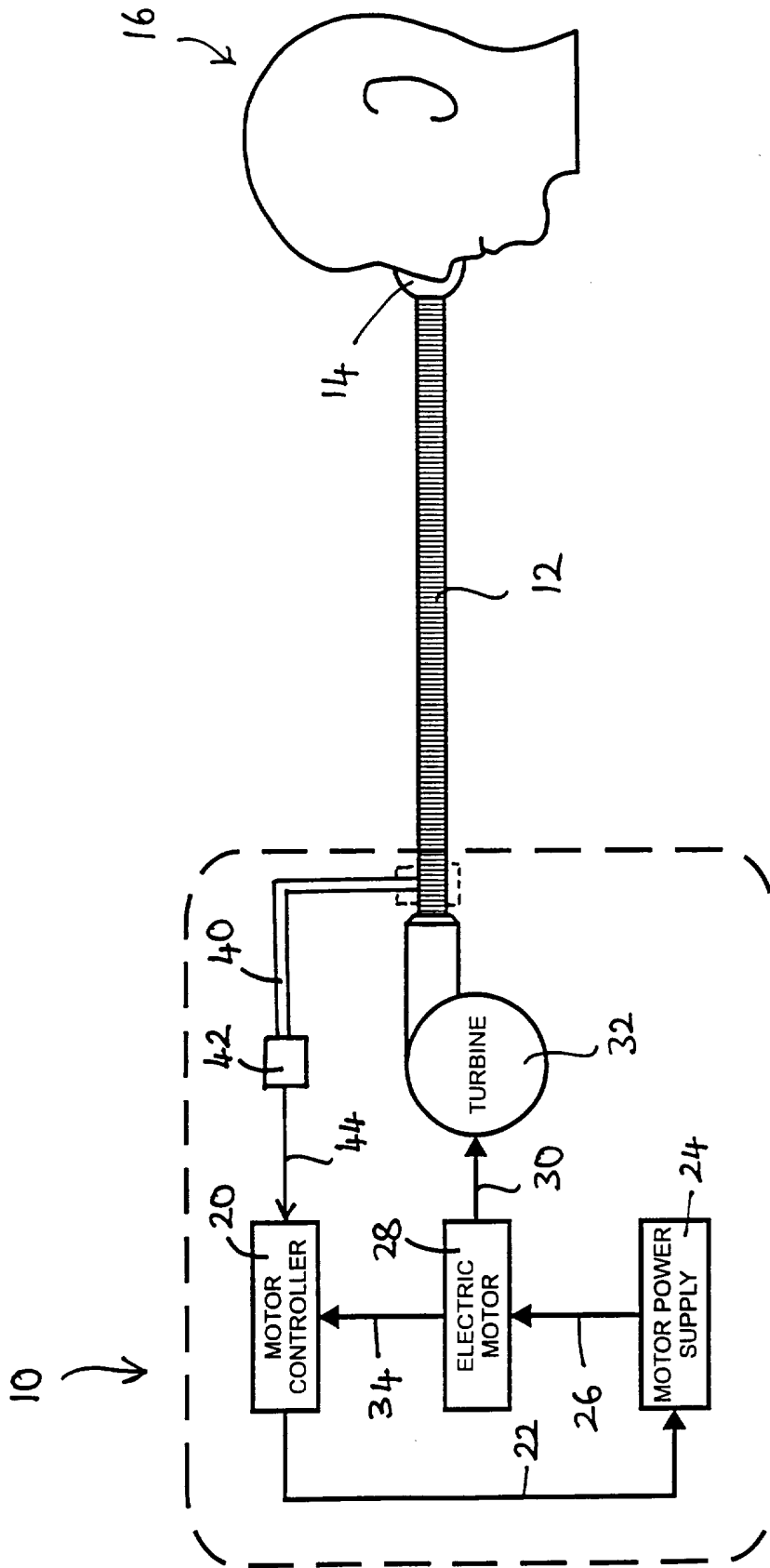


FIG. 1

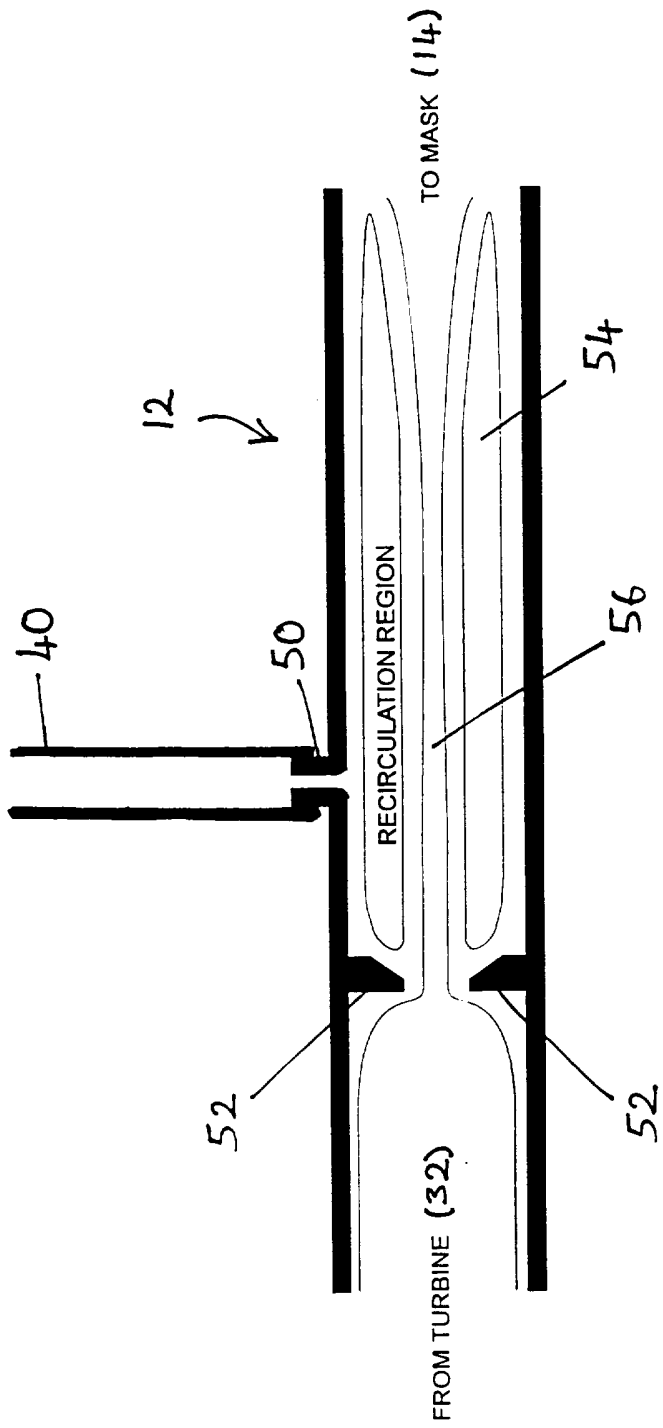


FIG. 2

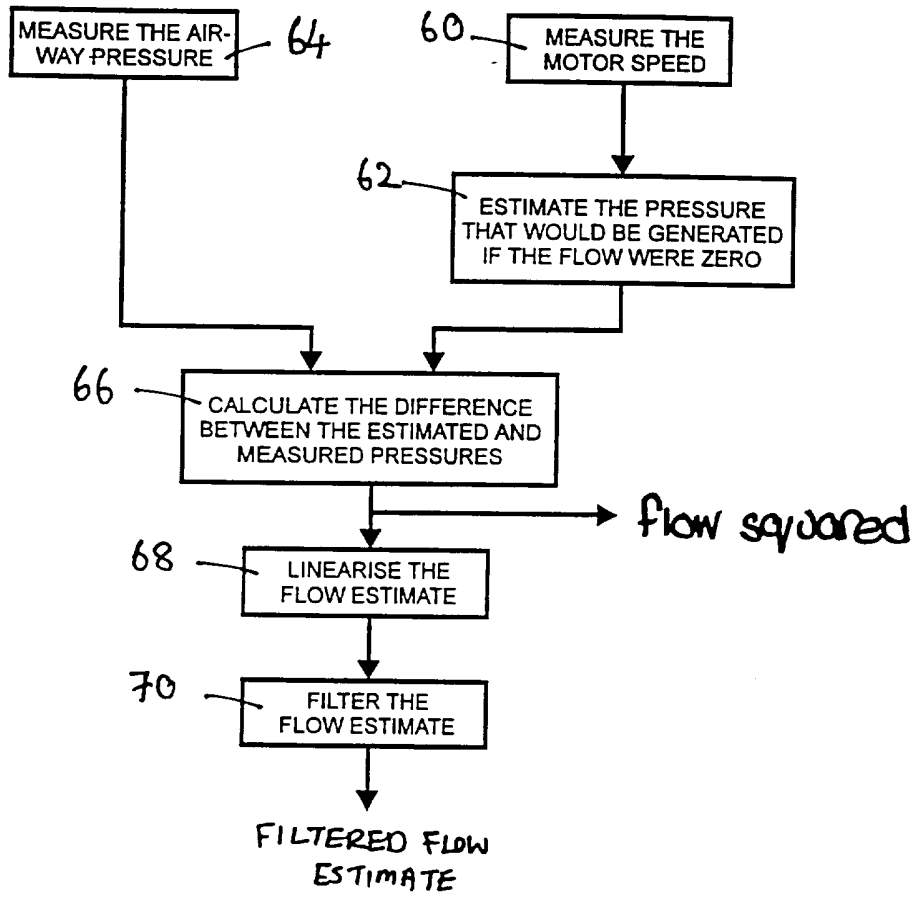


FIG. 3

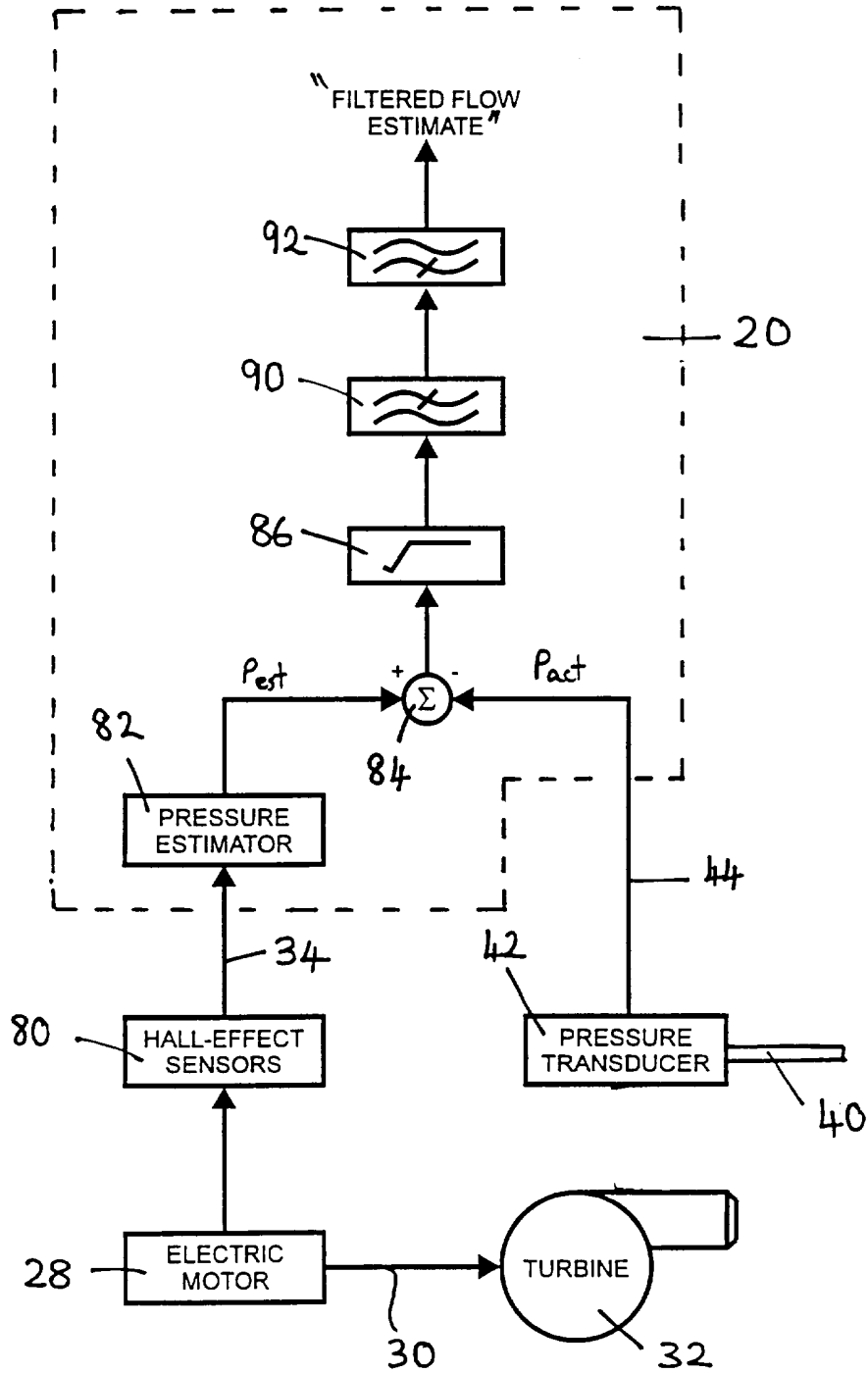


FIG. 4

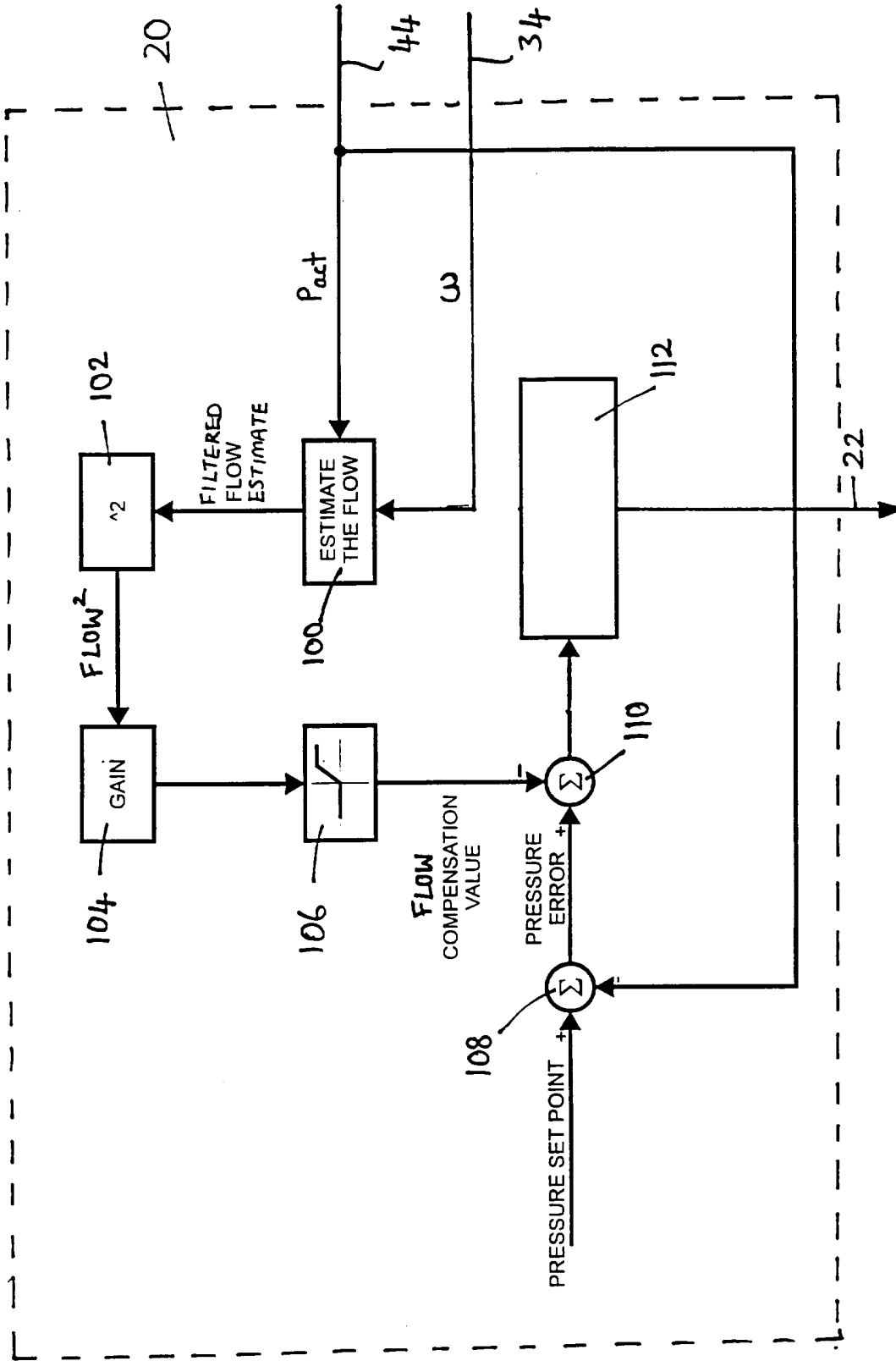


FIG. 5

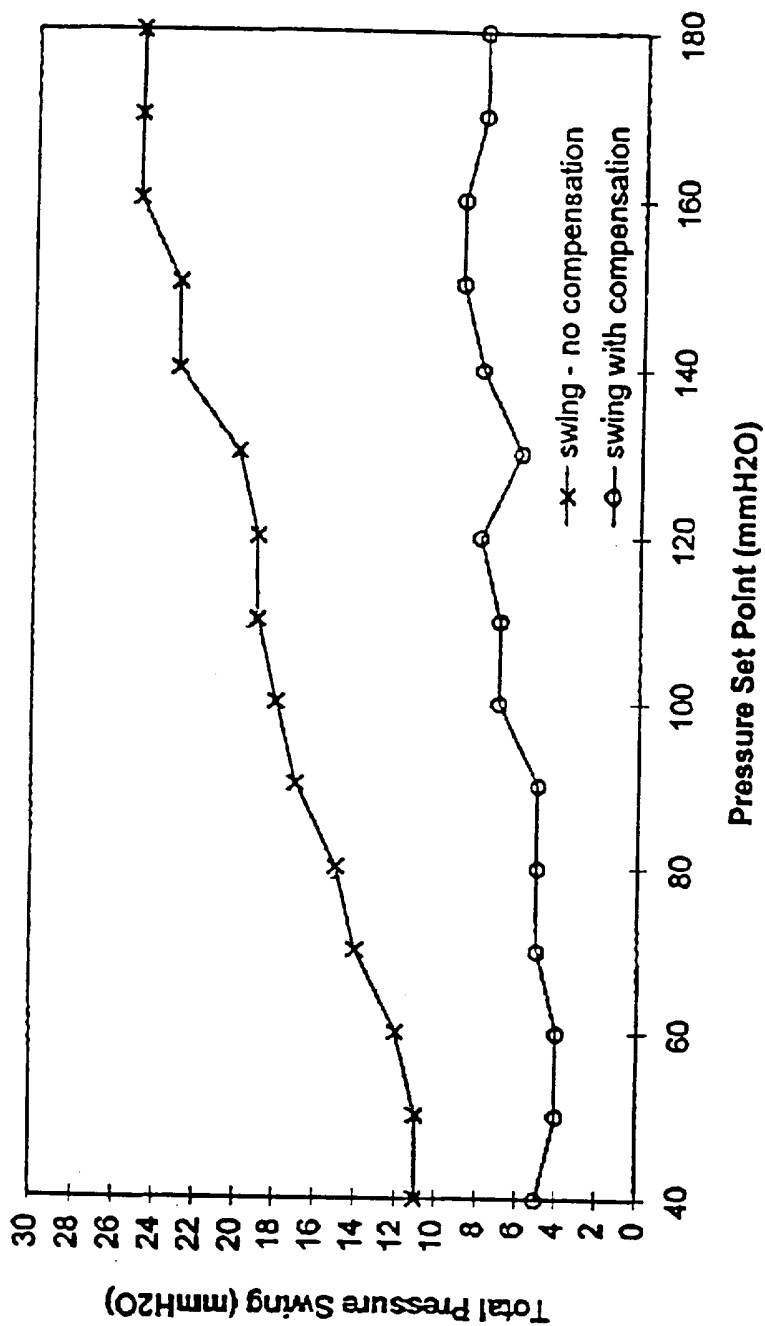
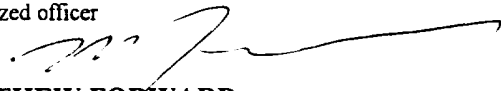


FIG. 6

INTERNATIONAL SEARCH REPORT

International Application No.
PCT/AU 96/00580

A. CLASSIFICATION OF SUBJECT MATTER		
Int Cl ⁶ : A61M 16/00 F04B 49/06 G01F 15/02		
According to International Patent Classification (IPC) or to both national classification and IPC		
B. FIELDS SEARCHED		
Minimum documentation searched (classification system followed by classification symbols) A61M 16/00 A61B 5/08, 5/087, 5/09 A62B 7/00 F04B 49/06, 49/08 F16K 31/02 G01F 1/34, 1/50, 15/00, 15/02 G01L 13/00, 13/06		
Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched AU IPC : as above		
Electronic data base consulted during the international search (name of data base and, where practicable, search terms used) DERWENT JAPIO		
C. DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
A	GB 1432572 A (F. HOFFMAN - LA ROCHE & CO AKTIENGESELLSCHAFT) 22 April 1976 page 1 lines 59-80, page 2 lines 101-121, page 6 lines 115 to page 7 line 14, page 8 lines 34 to 61	8-9
X	US 3985467 A (LEFFERSON) 12 October 1976 column 2 line 53 to column 3 line 55	1-3, 5, 6, 8-12
Y		7
X	US 4795314 A (PRYBELLA et. al.) 3 January 1989 column 1 line 28 to column 2 line 14, column 5 lines 20 to 31	8, 9
<input checked="" type="checkbox"/> Further documents are listed in the continuation of Box C <input checked="" type="checkbox"/> See patent family annex		
* Special categories of cited documents: "A" document defining the general state of the art which is not considered to be of particular relevance "E" earlier document but published on or after the international filing date "L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified) "O" document referring to an oral disclosure, use, exhibition or other means "P" document published prior to the international filing date but later than the priority date claimed "T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention "X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone "Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art "&" document member of the same patent family		
Date of the actual completion of the international search 23 October 1996		Date of mailing of the international search report 30 Oct 1996
Name and mailing address of the ISA/AU AUSTRALIAN INDUSTRIAL PROPERTY ORGANISATION PO BOX 200 WODEN ACT 2606 AUSTRALIA Facsimile No.: (06) 285 3929		Authorized officer  MATTHEW FORWARD Telephone No.: (06) 283 2606

INTERNATIONAL SEARCH REPORT

International Application No.
PCT/AU 96/00580

C (Continuation) DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X Y	US 4957107 A (SIPIN) 18 September 1990 column 2 line 61 to column 3 line 36, column 4 line 60 to column 5 line 15	1-3, 5-6, 8-12 7
Y	WO 93/24169 A (COTNER et. al.) 9 December 1993 pages 2 and 4	7
A	Derwent Abstract Accession No. 95-035038/05, Class S01, S02, RU 2012848 C (ENERGOMASH RES PORODN ASSOC) 15 May 1994 Abstract	1
X	EP 656216 A2 (& AU 79174/94 A) (RESCARE LIMITED) 7 June 1995 column 3 line 16 to column 5 line 47	6, 7
P, X	WO 96/16688 A (NELLCOR PURITAN BENNETT INCORPORATED) 6 June 1996 page 5 lines 1 to 28, page 6 line 27 to page 7 line 3	8-9
P, A	US 5540220 A (GROPPER et. al.) 30 July 1996 column 2 line 63 to column 3 line 43	

INTERNATIONAL SEARCH REPORT

International Application No.
PCT/AU 96/00580

Box 1 Observations where certain claims were found unsearchable (Continuation of item 1 of first sheet)

This International Search Report has not been established in respect of certain claims under Article 17(2)(a) for the following reasons:

1. Claims Nos.:
because they relate to subject matter not required to be searched by this Authority, namely:

2. Claims Nos.:
because they relate to parts of the international application that do not comply with the prescribed requirements to such an extent that no meaningful international search can be carried out, specifically:

3. Claims Nos.:
because they are dependent claims and are not drafted in accordance with the second and third sentences of Rule 6.4(a)

Box II Observations where unity of invention is lacking (Continuation of item 2 of first sheet)

This International Searching Authority found multiple inventions in this international application, as follows:

Independent claims 1, 6 and 7 define estimation of the flow of a breathable gas using the actual pressure generated by a turbine, the rotational speed of the turbine and an estimated pressure based on this speed. Claim 8 by contrast is concerned with reducing pressure swings at the mask of a respirator by adjusting the pressure control by a scaled flow factor.

1. As all required additional search fees were timely paid by the applicant, this international search report covers all searchable claims
2. As all searchable claims could be searched without effort justifying an additional fee, this Authority did not invite payment of any additional fee.
3. As only some of the required additional search fees were timely paid by the applicant, this international search report covers only those claims for which fees were paid, specifically claims Nos.:

4. No required additional search fees were timely paid by the applicant. Consequently, this international search report is restricted to the invention first mentioned in the claims; it is covered by claims Nos.:

Remark on Protest

- The additional search fees were accompanied by the applicant's protest.
 No protest accompanied the payment of additional search fees.

INTERNATIONAL SEARCH REPORT

Information on patent family members

International Application No.

PCT/AU 96/00580

This Annex lists the known "A" publication level patent family members relating to the patent documents cited in the above-mentioned international search report. The Australian Patent Office is in no way liable for these particulars which are merely given for the purpose of information.

Patent Document Cited in Search Report		Patent Family Member					
GB	1432572	AU	52957/73	BE	797297	CH	549392
		DE	2314356	ES	412991	FR	2178057
		IL	41617	IT	979627	JP	49013994
		NL	7304255				
US	3985467						
US	4795314	AU	21083/88	CA	1303702	DE	3828620
		FR	2619866	GB	2208949	IT	1223784
		JP	1110885				
US	4957107	EP	419551	WO	8910768		
WO	93/24169						
RU	2012848						
EP	656216						
WO	96/16688	AU	41650/96	US	5495848		
US	5540220						
END OF ANNEX							