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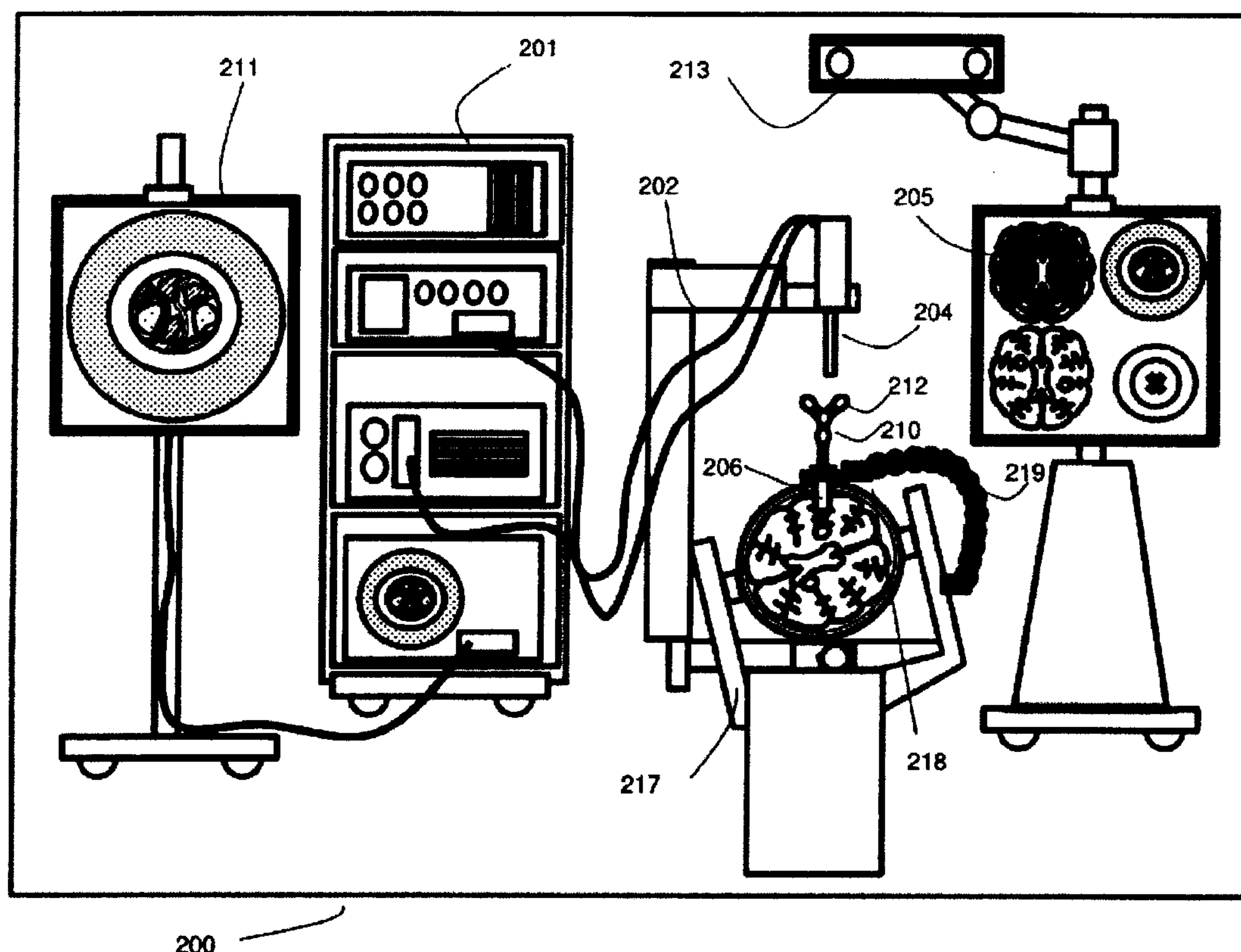
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(54) **Titre : SYSTEMES ET PROCEDES DE NAVIGATION ET DE SIMULATION DE THERAPIE MINI-INVASIVE**

(54) **Title: SYSTEMS AND METHODS FOR NAVIGATION AND SIMULATION OF MINIMALLY INVASIVE THERAPY**



(57) **Abrégé/Abstract:**

Disclosed herein is navigation and simulation systems and methods for minimally invasive therapy in which the navigation system imports a planning method using patient specific pre-operative images. The navigation system uses intraoperative imaging during the medical procedure to update the preoperative images and provides images of tracked surgical tools along the surgical path prepared from the preoperative images.

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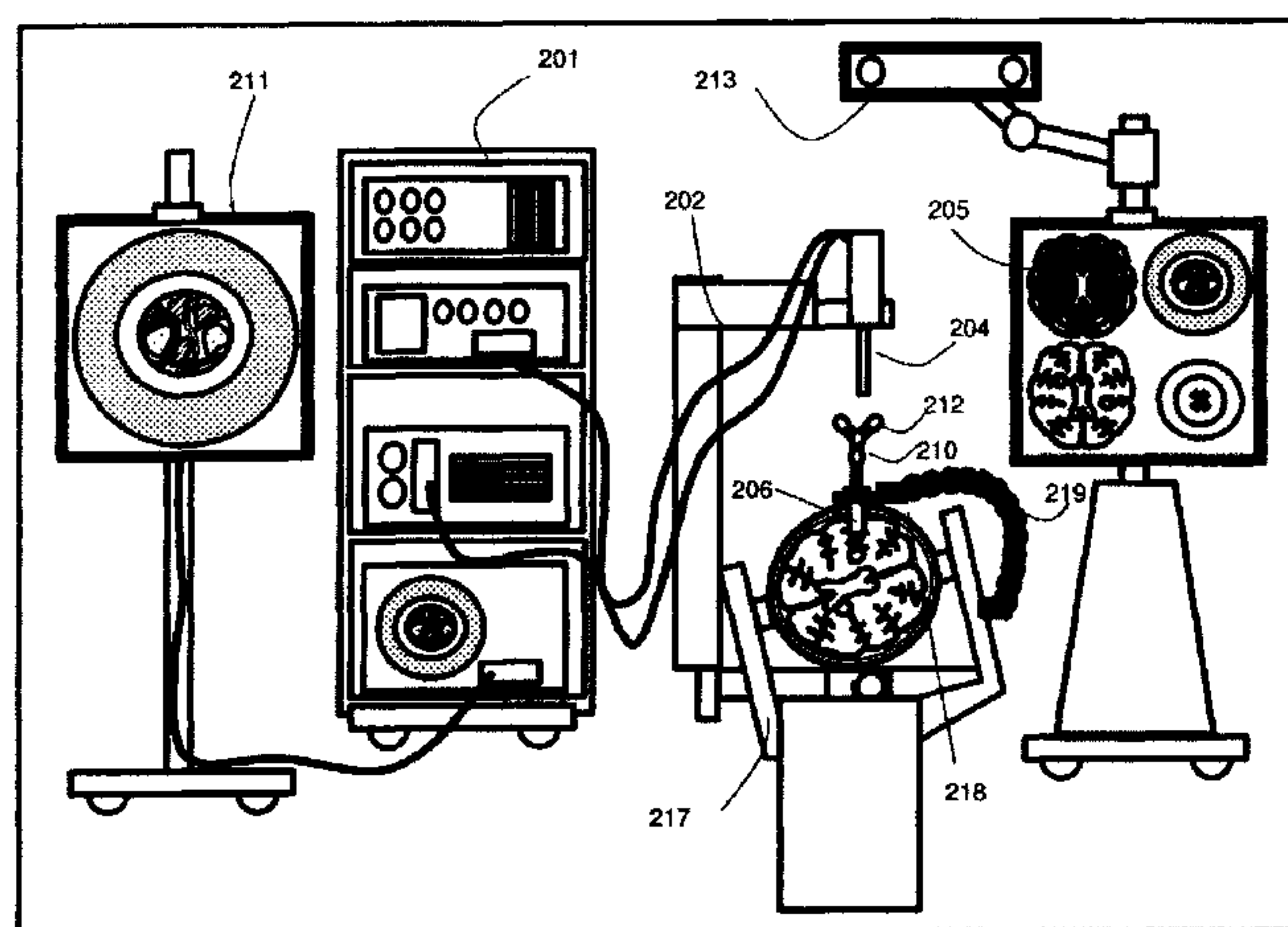
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(54) Title: SYSTEMS AND METHODS FOR NAVIGATION AND SIMULATION OF MINIMALLY INVASIVE THERAPY



200

Figure 2

(57) Abstract: Disclosed herein is navigation and simulation systems and methods for minimally invasive therapy in which the navigation system imports a planning method using patient specific pre-operative images. The navigation system uses intraoperative imaging during the medical procedure to update the preoperative images and provides images of tracked surgical tools along the surgical path prepared from the preoperative images.

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SYSTEMS AND METHODS FOR NAVIGATION AND SIMULATION OF MINIMALLY INVASIVE THERAPY

FIELD

The present disclosure relates to navigation systems and methods for minimally invasive therapy and image guided medical procedures.

BACKGROUND

Minimally invasive neuro-surgical procedures require geometrically accurate, and patient-registered, imaging data to facilitate tissue differentiation and targeting. Thus far, true integration of imaging (pre-surgical and intra-operative), surgical access, and resection devices has not been accomplished. Medical devices remain separate systems, and the surgeon is required to cognitively integrate the information.

Pre-operative imaging data such as Magnetic Resonance Imaging (MRI), Computerized Tomography (CT) and Positron Emission Tomography (PET), is integrated into the surgical room statically through a viewing station, or dynamically through a navigation system. The navigation system registers devices to a patient, and a patient to the pre-operative scans, allowing for instruments to be viewed on a monitor in the context of the pre-operative information.

Intra-operative imaging systems primarily consist of microscopes, endo-scopes, or external video scopes. These are optical instruments that acquire, record and display optical wavelength imaging (2D, or stereoscopic) that is typically acquired at an increased resolution compared to what can be seen with the surgeon's unassisted eye. This optical information is typically

displayed on a screen for the surgeon to view as a video feed, while the navigated MRI/CT/PET data would be presented on a separate screen.

Some attempts have been made to offer a small window on the navigation screen to show the optical video, or likewise showing overlays from the navigation screen on the optical video. Accurate registration between the modalities, effective interface between the surgeon and the devices, and true integration of the devices has remained elusive.

Port-based surgery is a minimally invasive surgical technique where a port is introduced to access the surgical region of interest using surgical tools. Unlike other minimally invasive techniques, such as laparoscopic techniques, the port diameter is larger than tool diameter. Hence, the tissue region of interest is visible through the port. Accordingly, exposed tissue in a region of interest at a depth few centimetres below the skin surface, and accessible through a narrow corridor in the port. Several problems generally preclude or impair the ability to perform port-based navigation in an intraoperative setting. For example, the position of the port axis relative to a typical tracking device (TD) is a free and uncontrolled parameter that prohibits the determination of access port orientation. Furthermore, the limited access available due to the required equipment for the procedure causes indirect access port tracking to be impractical and unfeasible. Also, the requirement for angulation of the access port to access many areas within the brain during a procedure makes navigation of the access port a difficult and challenging problem that has not yet been addressed.

Further, a recent paper by Stieglitz et al. [Stieglitz, Lennart Henning, et al. "The silent loss of neuronavigation accuracy: a systematic

retrospective analysis of factors influencing the mismatch of frameless stereotactic systems in cranial neurosurgery." *Neurosurgery* 72.5 (2013): 796-807.] highlights the need for accurate navigation, wherein after patient registration, there is an ongoing loss of neuronavigation accuracy due to other mitigating factors related to the surgical procedure (i.e., draping, attachment of skin retractors, and duration of surgery). Surgeons should be aware of this silent loss of accuracy when using navigation systems.

Thus, there is a need for a system and method to integrate and update pre-operative and intra-operative plans into navigation systems for minimally invasive surgical procedures.

SUMMARY

Disclosed herein is a navigation method and system used to execute a surgical plan during brain medical procedures. These procedures may include port based surgery using a port with an introducer, deep brain stimulation or brain biopsy using needles. The navigation system is configured to utilize a plan based on a multi-segment path trajectory previously prepared based on pre-operative anatomical information of the patient's brain. This plan is imported into the navigation software module. Prior to the procedure commencing, the brain is registered with its pre-operative anatomical information. Once the craniotomy has been performed, the navigation method and system displays an overlay image of the brain and the multipoint path trajectory. In addition it provides a **guidance mechanism** to assist the surgeon in aligning the surgical tool (port, biopsy

needle, catheter etc.) coaxially along the first path trajectory segment. Using port based surgery as an example, once the port is aligned with the first path trajectory segment the surgeon begins the cannulation procedure and moves the port introducer along the first segment while the system and method assists the surgeon in remaining consistently coaxial with the path segment and displays to the surgeon the distance of the introducer along the first segment until the end of the segment is reached. The surgeon then changes direction to follow the second trajectory segment. The process is repeated until the target location is reached.

The method and system provides the surgeon with positional information of the patient's anatomy of interest throughout the course of the medical procedure using video overlay (i.e. allowing the surgeon to see the brain through the drapes and therefore know his/her orientation relative to the patient). This allows the surgeon to more accurately identify potential locations of anatomical structures of the brain intra-operatively as opposed to performing the procedure without a rendered overlay of the anatomical part. The system and method allows the surgeon to confirm that they have the correct anatomical data of the patient more effectively than presently used systems. This is because in the present method and system the imaged anatomy is rendered onto the real-time imaging of the patient anatomy allowing the surgeon to compare the rendered image of the anatomical part with the real anatomical part, for example, comparing the sulci locations during a port procedure.

The method and system provides for tracking of multiple tools during surgery relative to the brain so the surgeon is not "flying blind". For example

the system can track the port as well as any tools being used in conjunction with the port, such as a resection tool in case of tumor resection, whereas presently used systems track only a pointer tool.

The navigation method and system provides a setup for the surgery to the surgical team based on a predetermined plan (i.e. setup of the head clamp, position of patient, tracking device, etc.) to prevent readjustments of such elements during surgery. The navigation method and system is configured to adaptively update a section of a larger pre-operative MRI image using a localized intraoperative MRI image (given that the brain is internally accessible from within the skull). The navigation method and system may provide positionally accurate maps (images) correlating intra-operative information acquired during surgery such as hyperspectral and Raman signatures to locations where the information were acquired. For example these signatures may be represented by spatially correlated color maps.

The above-described method and system, while primarily described for port based brain surgery, is not limited to port based brain surgery and is applicable to any surgery that utilizes a navigation system. Thus a port may not be used and the anatomical part may be any part of the anatomy. This system can be utilized with any animal other than and including humans.

A further understanding of the functional and advantageous aspects of the invention can be realized by reference to the following detailed description and drawings.

BRIEF DESCRIPTION OF THE DRAWINGS

Embodiments disclosed herein will be more fully understood from the following detailed description thereof taken in connection with the accompanying drawings, which form a part of this application, and in which:

Figure 1 shows an exemplary navigation system to support minimally invasive access port-based surgery.

Figure 2 is block diagram illustrating system components of a navigation system.

Figure 3A is a flow chart illustrating the processing steps involved in a port-based surgical procedure using a navigation system.

Figure 3B is a flow chart illustrating the processing steps involved in registering a patient for a port-based surgical procedure as outlined in **Figure 3A**.

Figure 4A illustrates an example embodiment of the navigation system software illustrating the Patient Positioning step.

Figure 4B illustrates an example embodiment of the navigation system software illustrating the Registration step.

Figure 4C illustrates an example embodiment of the navigation system software illustrating the Craniotomy step.

Figure 4D illustrates example embodiments of the navigation system software illustrating the Engagement step.

Figure 4E illustrates an example embodiment of the navigation system software illustrating the Cannulation step.

Figure 5 is an illustration tracking of tools in a port-based surgical procedure.

Figure 6A to 6D are illustrations of exemplary pointing tools with tracking markers.

Figure 6E is an illustration of an exemplary port with tracking markers.

Figure 7 is an illustration of an exemplary port and pointing tool with tracking markers.

Figure 8 is an illustration of an example system inclusive of all of its independent parts and what they would interact with.

Figure 9 is a block diagram showing system components and inputs for planning and scoring surgical paths as disclosed herein.

Figure 10 is a block diagram showing system components and inputs for navigation along the surgical paths produced by an exemplary planning system of **Figure 9**.

Figure 11A is a flow chart illustrating alternate processing steps involved in a port based surgical procedure using a navigation system.

Figure 11B is a flow chart illustrating processing steps involved in a brain biopsy surgical procedure using a navigation system.

Figure 11C is a flow chart illustrating the processing steps involved in a deep-brain stimulation procedure using a navigation system.

Figure 11D a flow chart illustrating the processing steps involved in a catheter / shunt placement procedure using a navigation system.

DETAILED DESCRIPTION

Various embodiments and aspects of the disclosure will be described with reference to details discussed below. The following description and drawings are illustrative of the disclosure and are not to be construed as

limiting the disclosure. Numerous specific details are described to provide a thorough understanding of various embodiments of the present disclosure. However, in certain instances, well-known or conventional details are not described in order to provide a concise discussion of embodiments of the present disclosure.

The systems and methods described herein are useful in the field neurosurgery, including oncological care, neurodegenerative disease, stroke, brain trauma and orthopedic surgery; however persons of skill will appreciate the ability to extend these concepts to other conditions or fields of medicine. It should be noted that the surgical process is applicable to surgical procedures for brain, spine, knee and any other region of the body that will benefit from the use of an access port or small orifice to access the interior of the human body.

Various apparatuses or processes will be described below to provide examples of embodiments of the navigation method and system disclosed herein. No embodiment described below limits any claimed embodiment and any claimed embodiments may cover processes or apparatuses that differ from those described below. The claimed embodiments are not limited to apparatuses or processes having all of the features of any one apparatus or process described below or to features common to multiple or all of the apparatuses or processes described below. It is possible that an apparatus or process described below is not an embodiment of any claimed invention.

Furthermore, numerous specific details are set forth in order to provide a thorough understanding of the embodiments described herein.

However, it will be understood by those of ordinary skill in the art that the embodiments described herein may be practiced without these specific details. In other instances, well-known methods, procedures and components have not been described in detail so as not to obscure the embodiments described herein.

Figure 1 shows an exemplary navigation system to support minimally invasive access port-based surgery. **Figure 1** illustrates a perspective view of a minimally invasive port based surgical procedure. As shown in **Figure 1**, surgeon **101** conducts a minimally invasive port-based surgery on a patient **102** in an operating room (OR) environment. A navigation system **200** comprising an equipment tower, tracking system, displays and tracked instruments assist the surgeon **101** during his procedure. An operator **103** is also present to operate, control and provide assistance for the navigation system **200**.

Figure 2 is block diagram illustrating system components of an exemplary navigation system. Navigation system **200** in **Figure 2** includes a monitor **211** for displaying a video image, an equipment tower **201**, a mechanical arm **202**, which supports an optical scope **204**. Equipment tower **201** is mounted on a frame (i.e., a rack or cart) and may contain a computer, planning software, navigation software, a power supply and software to manage the automated arm and tracked instruments. The exemplary embodiment envisions the equipment tower **201** as a single tower configuration with dual displays (**211**, **205**), however, other configurations may also exist (i.e., dual tower, single display, etc.). Furthermore, equipment tower **201** may also be configured with a UPS (universal power

supply) to provide for emergency power, in addition to a regular AC adapter power supply.

The patient's brain is held in place by a head holder **217** and inserted into the head is an access port **206** and introducer **210**. The introducer **210** may also be considered a pointing tool. The introducer **210** may be tracked using a tracking system **213**, which provides position information for the navigation system **200**. Tracking system **213** may be a 3D optical tracking stereo camera similar to one made by Northern Digital Imaging (NDI). Location data of the mechanical arm **202** and port **206** may be determined by the tracking system **213** by detection of fiducial markers **212** placed on these tools. A secondary display **205** may provide output of the tracking system **213**. The output may be shown in axial, sagittal and coronal views (or views oriented relative to the tracked instrument such as perpendicular to tool tip, in-plane of tool shaft, etc.) as part of a multi-view display.

Minimally invasive brain surgery using access ports is a recently conceived method of performing surgery on brain tumors. In order to introduce an access port into the brain, an introducer **210** with an atraumatic tip may be positioned within the access port and employed to position the access portion within the head. As noted above, the introducer **210** may include fiducial markers **212** for tracking, as presented in **Figure 2**. The fiducial markers **212** may be reflective spheres in the case of optical tracking systems or pick-up coils in the case of electromagnetic tracking systems. The fiducial markers **212** are detected by the tracking system **213** and their respective positions are inferred by the tracking software.

Once inserted into the brain, the introducer **210** may be removed to allow for access to the tissue through the central opening of the access port. However, once introducer **210** is removed, the access port can no longer be tracked. Accordingly, the access port may be indirectly tracked by additional pointing tools configured for identification by the navigation system **200**.

In **Figure 2**, a guide clamp **218** for holding the access port **206** may be provided. Guide clamp **218** can optionally engage and disengage with access port **206** without needing to remove the access port from the patient. In some embodiments, the access port can slide up and down within the clamp while in the closed position. A locking mechanism may be attached to or integrated with the guide clamp, and can optionally be actuated with one hand, as described further below.

Referring again to **Figure 2**, a small articulated arm **219** may be provided with an attachment point to hold guide clamp **218**. Articulated arm **219** may have up to six degrees of freedom to position guide clamp **218**. Articulated arm **219** may be attached or attachable to a point based on patient head holder **217**, or another suitable patient support, to ensure when locked in place, guide clamp **218** cannot move relative to the patient's head. The interface between guide clamp **218** and articulated arm **219** may be flexible, or optionally locked into place. Flexibility is desired so the access port can be moved into various positions within the brain, but still rotate about a fixed point.

An example of such a linkage that can achieve this function is a slender bar or rod. When the access port **206** is moved to various positions, the bar or rod will oppose such a bend, and move the access port **206** back

to the centered position. Furthermore, an optional collar may be attached to the linkage between the articulated arm, and the access port guide, such that when engaged, the linkage becomes rigid. Currently, no such mechanisms exist to enable positioning an access port in such a manner.

In a surgical operating room (or theatre), setup of a navigation system may be complicated; there may be many pieces of equipment associated with the surgical procedure, as well as, the navigation system. Further, setup time increases as more equipment is added. One possible solution, is an extension of the exemplary navigation system **200** outlined in **Figure 2**, where two additional wide-field cameras are implemented with video overlay information. One wide-field camera may be mounted on optical scope **204**, and a second wide-field camera may be mounted on the navigation system **213**. Alternately, in the case of an optical tracking system a video image can possibly be extracted directly from the camera within the tracking system 213. Video overlay information can then be inserted into the images, where the video overlay may provide the following information:

- illustrate physical space and confirm tracking system registration alignment

- illustrate range of motion of a robot used to hold the external scope.

- guide head positioning and patient positioning.

Figure 3A is a flow chart illustrating the processing steps involved in a port-based surgical procedure using a navigation system. The first step involves importing the port-based surgical plan (step **302**). A detailed description of a process to create and select a surgical plan is outlined in the disclosure “**PLANNING, NAVIGATION AND SIMULATION SYSTEMS AND**

METHODS FOR MINIMALLY INVASIVE THERAPY” International PCT Patent Publication WO 2014/139024 based on International PCT Patent Application Serial No. PCT/CA2014/050272.

An exemplary plan, as outlined above, may compose of pre-operative 3D imaging data (i.e., MRI, CT, Ultrasound, etc) and overlaying on it, received inputs (i.e., sulci entry points, target locations, surgical outcome criteria, additional 3D image data information) and displaying one or more trajectory paths based on the calculated score for a projected surgical path. It should be noted that 3D images may be comprised of 3 spatial dimensions. In another embodiment, the 3 dimensions may be comprised of 2 spatial dimensions (as in the case of MR ‘slice’ images as acquired by conventional MR equipment) and time as the third dimension. A further embodiment may include 3 spatial dimensions and time as the fourth dimension of the data set. Some imaging modalities and estimation methods, such as Diffusion Tensor Imaging data, may contain more than four dimensions of information at each spatial location. The aforementioned surgical plan may be one example; other surgical plans and / or methods may also be envisioned and may form the planning input into the present guidance and navigation system.

Figure 9 is a block diagram showing system components and inputs for planning and scoring surgical paths as disclosed herein as disclosed in International PCT Patent Publication WO 2014/139024 as noted above.

Figure 10 is a block diagram showing system components and inputs for navigation along the surgical paths produced by an exemplary planning system of **Figure 9**.

More specifically, **Figure 10** shows an embodiment of the present method and system, for use as an intra-operative multi-modal surgical planning and navigation system and method. The system and method can be used as a surgical planning and navigation tool in the pre-operative and intra-operative stages. Persons of skill will appreciate that the data input(s) of the surgical planning steps and surgical procedures described in **Figure 9**, can be used as input(s) to the intra-operative navigation stage described in **Figure 10**.

The navigation system of **Figure 10** provides a user, such as a surgeon, with a unified means of navigating through a surgical region by utilizing pre-operative data input(s) and updated intra-operative data input(s). The processor(s) of system and methods are programmed with instructions/algorithms **11** to analyze pre-operative data input(s) and intra-operative data input(s) to update surgical plans during the course of surgery.

For example, if intra-operative input(s) in the form of newly acquired images identified a previously unknown nerve bundle or fiber track, these input(s) can, if desired, be used to update the surgical plan during surgery to avoid contacting the nerve bundle. Persons of skill will appreciate that intra-operative input(s) may include a variety input(s) including local data gathered using a variety of sensor(s).

In some embodiments, the system and methods of **Figure 10** may provide continuously updated intra-operative input(s) in the context of a specific surgical procedure by means of intraoperative imaging sensor(s) to validate tissue position, update tissue imaging after tumor resection and update surgical device position during surgery.

The systems and methods may provide for re-formatting of the image, for example, to warn of possible puncture of critical structures with the surgical tools during surgery, or collision with the surgical tool during surgery. In addition, the embodiments disclosed herein may provide imaging and input updates for any shifts that might occur due to needle deflection, tissue deflection or patient movement as well as algorithmic approaches to correct for known imaging distortions. The magnitude of these combined errors is clinically significant and may regularly exceed 2 cm. Some the most significant are MRI based distortions such gradient non-linearity, susceptibility shifts, eddy current artifacts which may exceed 1cm on standard MRI scanners (1.5T and 3.0T systems).

Persons of skill will appreciate that a variety of intraoperative imaging techniques can be implemented to generate intra-operative input(s) including anatomy specific MRI devices, surface array MRI scans, endo-nasal MRI devices, anatomy specific US scans, endo-nasal US scans, anatomy specific CT or PET scans, port-based or probe based photo-acoustic imaging, as well as optical imaging done with remote scanning, or probe based scanning.

Referring again to **Figure 3A**, once the plan has been imported into the navigation system (step **302**), the patient is affixed into position using a head or body holding mechanism. The head position is also confirmed with the patient plan using the navigation software (step **304**). **Figure 4A** illustrates an example embodiment of the navigation system software illustrating the Patient Positioning step **304**. In this embodiment, the plan is reviewed and the patient positioning is confirmed to be consistent with

craniotomy needs. Furthermore, a procedure trajectory may be selected from a list of planned trajectories produced in the planning procedure.

Returning to **Figure 3A**, the next step is to initiate registration of the patient (step **306**). The phrase "registration" or "image registration" refers to the process of transforming different sets of data into one coordinate system.

Registration of the patient to a base reference frame, as outlined in **Figure 3A**, may occur in many ways. A few traditional methods or registration may include:

- a) Identify features (natural or engineered) on the MR and CT images and point to those same features in the live scene using a pointer tool that is tracked by the tracking system.
- b) Trace a line on the curved profile of the patient's face or forehead with a pointer tool that is tracked by the tracking system. Match this curved profile to the 3D MR or CT volume.
- c) Apply a tool of known geometry to the face. This tool has the active or passive targets tracked by the tracking system.
- d) Use a surface acquisition tool based on structured light. The extracted surface is then matched to the 3D MR or CT volume using standard techniques.

Those skilled in the art will appreciate that there are numerous registration techniques available and one or more of them may be used in the present application. Non-limiting examples include intensity-based methods which compare intensity patterns in images via correlation metrics, while feature-based methods find correspondence between image features

such as points, lines, and contours. Image registration algorithms may also be classified according to the transformation models they use to relate the target image space to the reference image space. Another classification can be made between single-modality and multi-modality methods. Single-modality methods typically register images in the same modality acquired by the same scanner/sensor type, for example, a series of MR images can be co-registered, while multi-modality registration methods are used to register images acquired by different scanner/sensor types, for example in MRI and PET.

In the present disclosure multi-modality registration methods are used in medical imaging of the head/brain as images of a subject are frequently obtained from different scanners. Examples include registration of brain CT/MRI images or PET/CT images for tumor localization, registration of contrast-enhanced CT images against non-contrast-enhanced CT images, and registration of ultrasound and CT.

Figure 3B is a flow chart illustrating the further processing steps involved in registration as outlined in **Figure 3A**. In this exemplary embodiment, registration can be completed using fiducial touchpoints (340) captured by a pointing tool as described further in **Figure 6A to 6D**. If fiducial touchpoints (340) is contemplated, the process involves first identifying fiducials on images (step 342), then touching the fiducial touchpoints (340) with a tracked instrument (344). Next, the navigation system computes the registration to reference markers (step 346).

Registration can also be completed by conducting a surface scan procedure (350). The first step involves scanning the face using a 3D

scanner (step **352**). The next step is to extract the face surface from MR / CT data (step **354**). Finally, surfaces are matched to determine registration datapoints.

Upon completion of either the fiducial touchpoints (**340**) or surface scan (**350**) procedures, the data extracted is computed and used to confirm registration (step **308**). **Figure 4B** is a screenshot of the navigation system software illustrating the Registration step using fiducial touchpoints.

In a further embodiment, recovery of loss of registration may also be provided. A detailed description of a process to create and select a surgical plan is outlined in the disclosure "**SYSTEM AND METHOD FOR DYNAMIC VALIDATION, CORRECTION OF REGISTRATION FOR SURGICAL NAVIGATION**" International PCT Patent Publication WO 2014/139019 based on International PCT Patent Application Serial No. PCT/CA2014/050266.

As disclosed therein, during a navigation procedure a handheld instrument is tracked using a tracking system, and a representation of the instrument's position and orientation may be provided and displayed as an overlay on a previously acquired or current image (such as a three-dimensional scan) of a patient's anatomy obtained with an imaging device or system (such as ultrasound, CT or MRI). To achieve this, a registration is needed between the coordinate frame of a tracking system, the physical location of the patient in space, and the coordinate frame of the corresponding image of the patient. This registration is typically obtained relative to a tracked reference marker, which is placed in a fixed position relative to the patient anatomy of interest and thus can be used as a fixed

reference for the anatomy. Generally this can be accomplished by attaching the reference to a patient immobilization frame (such as a clamp for skull fixation in neurosurgery), which itself is rigidly attached to the patient. However, the reference may be held to the frame, for example, through an arm, which can be bumped and accidentally moved, which creates a loss of registration.

Additionally, since the reference marker must be positioned so that it is visible by the navigation hardware (typically requiring line-of-sight for optical tracking, or otherwise within the observation or communication field of the tracking system), this tends to position the reference such that it is in the open thus more susceptible to accidental interaction and loss of registration. In situations of lost registration, a surgical procedure tends to be stopped while a new registration is computed, although this may not always be possible if, for example, the registration fiducial points or patient skin surface are no longer accessible due to the progression of the surgical procedure, and thus creating a need for a full re-registration or, in some cases even disabling navigation for the remainder of the procedure.

Once registration is confirmed (step **308**), the patient is draped (step **310**). Typically draping involves covering the patient and surrounding areas with a sterile barrier to create and maintain a sterile field during the surgical procedure. The purpose of draping is to eliminate the passage of microorganisms (i.e., bacteria) between non-sterile and sterile areas.

Upon completion of draping (step **310**), the next steps is to confirm patient engagement points (step **312**) and then prep and plan craniotomy

(step **314**). **Figure 4C** illustrates an example embodiment of the navigation system software illustrating the prep and plan craniotomy step (step **314**).

Upon completion of the prep and planning of the craniotomy step (step **312**), the next step is to cut craniotomy (step **314**) where a bone flap is temporarily removed from the skull to access the brain (step **316**).

Registration data can be updated with the navigation system at this point (step **322**), such as by adding additional registration correspondence points within the craniotomy (e.g. the location of a visible blood vessel).

The next step is to confirm the engagement within craniotomy and the motion range (step **318**). Once this data is confirmed, the procedure advances to the next step of cutting the dura at the engagement points and identifying the sulcus (step **320**). **Figure 4D** illustrates example embodiments of the navigation system software illustrating the engagement steps (step **318** and **320**). Registration data can be updated with the navigation system at this point (step **322**), such as by adding additional registration correspondence points near the engagement point (e.g. a bifurcation of the entry sulcus). In an embodiment, by focusing the wide field camera's gaze on the surgical area of interest, this registration update can be manipulated to ensure the best match for that region, while ignoring any non-uniform tissue deformation affecting areas outside of the surgical field (of interest). Additionally, by matching overlay representations of tissue with an actual view of the tissue of interest, the particular tissue representation can be matched to the video image, and thus tending to ensure registration of the tissue of interest. For example, the embodiment can (either manually or automatically):

- match video of post craniotomy brain (i.e. brain exposed) with imaged sulcal map; and/or
- match video position of exposed vessels with image segmentation of vessels; and/or
- match video position of lesion or tumour with image segmentation of tumour; and/or
- match video image from endoscopy up nasal cavity with bone rendering of bone surface on nasal cavity for endonasal alignment.

Above method is described in detail in the co-pending PCT Patent Application No. PCT/CA2014/050272 with publication no. WO 2014/139024.

In other embodiments, multiple cameras can be used and overlaid with tracked instrument(s) views, and thus allowing multiple views of the data and overlays to be presented at the same time, which can tend to provide even greater confidence in a registration, or correction in more dimensions / views.

Thereafter, the cannulation process is initiated (step **324**).

Cannulation involves inserting a port into the brain, typically along a sulci path as identified in step **320**, along a trajectory plan. Cannulation is an iterative process that involves repeating the steps of aligning the port on engagement and setting the planned trajectory (step **332**) and then cannulating to the target depth (step **334**) until the complete trajectory plan is executed (step **324**). **Figure 4E** illustrates an example embodiment of the navigation system software illustrating the Cannulation steps.

The cannulation process (step **324**) may also support multi-point trajectories where a target (i.e., a tumour) may be accessed by pushing to intermediate points, then adjusting the angle to get to the next point in

planned trajectory. This process allows trajectories to skirt around tissue that one may want to preserve, or ensure staying within a sulcus to avoid damaging neighbouring tissue. Navigating multi-point trajectories may be accomplished by physically reorienting a straight port at different points along a (planned) path, or by having a flexible port that has a number of manipulatable bends that can be set along the path.

The surgeon then decannulates (step **326**) by removing the port and any tracking instruments from the brain. The surgeon then performs resection (step **328**) to remove part of the brain and / or tumour of interest. Finally, the surgeon closes the dura and completes the craniotomy (step **330**).

In a further embodiment, the navigation system relates to fiber structures of the brain (nerves, ligaments, etc) that can be re-imaged and registered so that it can be intra-operatively addressed using different modalities.

In a further embodiment, quantitative registration may also be addressed. Quantitative registration refers to the ability to measure an absolute quantitative metric and use that to register between imaging modalities. These quantitative metrics may include T1, T2, cell density, tissue density, tissue anisotropy, tissue stiffness, fluid flow per volume or area, electrical conductivity, pH, and pressure. **Figure 5** is an illustration of a port-based surgical procedure. In **Figure 5**, surgeon **501** is resecting a tumor out of the brain of a patient **502** through port **504**. External scope **505** is attached to mechanical arm **504**, and is used to view down port **504** at a

sufficient magnification to allow for enhanced visibility down port **504**. The output of external scope **505** view is depicted on a visual display.

Active or passive fiduciary spherical markers (**507** and **508**) may be placed on port **504** and / or external scope **505** to determine the location of these tools by the tracking system. The spheres are seen by the tracking system to give identifiable points for tracking. A tracked instrument is typically defined as a grouping of spheres - defining a rigid body to the tracking system. This is used to determine the position and pose in 3D of a tracked instrument. Typically, a minimum of 3 spheres are placed on a tracked tool to define the instrument. In the figures of this disclosure, 4 spheres are used to track each tool.

In a preferred embodiment, the navigation system may utilize reflectosphere markers in combination with an optical tracking system to determine spatial positioning of the surgical instruments within the operating field. The spatial position of automated mechanical arm(s) used during surgery may be also tracked in a similar manner. Differentiation of the types of tools and targets and their corresponding virtual geometrically accurate volumes could be determined by the specific orientation of the reflectospheres relative to one another giving each virtual object an individual identity within the navigation system. The individual identifiers would relay information to the system as to the size and virtual shape of the tool within the system. The identifier could also provide information such as the tool's central point, the tool's central axis, etc. The virtual tool may also be determinable from a database of tools provided to the navigation system. The marker positions could be tracked relative to an object in the operating

room such as the patient. Other types of markers that could be used would be RF, EM, LED (pulsed and un-pulsed), glass spheres, reflective stickers, unique structures and patterns, where the RF and EM would have specific signatures for the specific tools they would be attached to. The reflective stickers, structures and patterns, glass spheres, LEDs could all be detected using optical detectors, while RF and EM could be picked up using antennas. Advantages to using EM and RF tags would include removal of the line of sight condition during the operation, where using optical system removes the additional noise from electrical emission and detection systems.

In a further embodiment, printed or 3-D design markers could be used for detection by an auxiliary camera and / or external scope. The printed markers could also be used as a calibration pattern to provide distance information (3D) to the optical detector. These identification markers may include designs such as concentric circles with different ring spacing, and / or different types of bar codes. Furthermore, in addition to using markers, the contours of known objects (e.g., side of the port, top ring of the port, shaft of pointer tool, etc.) could be made recognizable by the optical imaging devices through the tracking system.

Figure 6A to 6D are illustrations of various perspective views of exemplary pointing tools with fiducial or tracking markers. Referring to **Figure 6A**, tracking marker **610** is placed on connector beam **615** attached to arm **620** of pointing tool **600**. A minimum of three (3) tracking markers **610**, and preferably four (4) markers, are placed on the tool **600** to track it with a tracking system. **Figure 6B to 6D** provide illustrations of other

embodiments of pointing tools with tracking markers **610** placed in various orientations and positions. For example, tracking tool **640** of **Figure 6B** is connected to a supporting arm structure **642** to which four tracking markers **610** are rigidly attached. Tracking tool **650** of **Figure 6C** is connected to a supporting arm structure **652**, having a different configuration to arm support structure **652** of **Figure 6B**, to which four tracking markers **610** are rigidly attached. Tracking tool **660** of **Figure 6D** is connected to a supporting arm structure **662** different configurations from structures **652**, **642** and **620**, to which four tracking markers **610** are rigidly attached.

Figure 6E illustrates various perspectives of an embodiment of an access port **680** where fiducial or tracking markers **610** are placed on an extended arm **682** that is firmly attached to the access port **680**. This arrangement enables clear visibility of the markers to the tracking device. Further, the extended arm **682** ensures that the markers **610** do not interfere with surgical tools that may be inserted through the access port **680**. The non-uniform structure of the support arm for the fiducial markers **610** enables the tracking software to discern both the position and orientation of the access port.

Figure 7 is an illustration of an exemplary embodiment of pointing tool **650**, with associated support arm structure **652** (as seen in **Figure 6C**) with associated fiducial markers **610**, inserted into a port **690** which has its own fiducials **692** on associated arm support structure **694**. Both the pointing tool and port are equipped with arms configured with tracking markers. These tools with tracking markers can then be tracked separately by the navigation system and differentiated as unique objects on the display.

Referring now to **Figure 8**, a block diagram of an example system configuration is shown. The example system includes control and processing unit **400** and a number of external components, shown below.

As shown in **Figure 8**, in one embodiment, control and processing unit **400** may include one or more processors **402**, a memory **404**, a system bus **406**, one or more input/output interfaces **408**, and a communications interface **410**, and storage device **412**. Control and processing unit **400** is interfaced with other external devices, such as tracking system **120**, data storage **442**, and external user input and output devices **444**, which may include, for example, one or more of a display, keyboard, mouse, foot pedal, microphone and speaker. Data storage **442** may be any suitable data storage device, such as a local or remote computing device (e.g. a computer, hard drive, digital media device, or server) having a database stored thereon. In the example shown in **Figure 8**, data storage device **442** includes identification data **450** for identifying one or more medical instruments **460** and configuration data **452** that associates customized configuration parameters with one or more medical instruments **460**. Data storage device **442** may also include preoperative image data **454** and/or medical procedure planning data **456**. Although data storage device **442** is shown as a single device in **Figure 8**, it will be understood that in other embodiments, data storage device **442** may be provided as multiple storage devices.

In a further embodiment, various 3D volumes, at different resolutions, may each be captured with a unique time-stamp and / or quality metric. This

data structure provides an ability to move through contrast, scale and time during the procedure and may also be stored in data storage device **442**.

Medical instruments **460** are identifiable by control and processing unit **400**. Medical instruments **460** may be connected to, and controlled by, control and processing unit **400**, or may be operated or otherwise employed independent of control and processing unit **400**. Tracking system **120** may be employed to track one or more of medical instruments and spatially register the one or more tracked medical instruments to an intraoperative reference frame.

Control and processing unit **400** is also interfaced with a number of configurable devices, and may intraoperatively reconfigure one or more of such devices based on configuration parameters obtained from configuration data **452**. Examples of devices **420**, as shown in the figure, include one or more external imaging device **422**, one or more illumination devices **424**, robotic arm **105**, one or more projection devices **428**, and one or more displays **115**.

Embodiments of the disclosure can be implemented via processor(s) **402** and/or memory **404**. For example, the functionalities described herein can be partially implemented via hardware logic in processor **402** and partially using the instructions stored in memory **404**, as one or more processing engines **470**. Example processing engines include, but are not limited to, user interface engine **472**, tracking engine **474**, motor controller **476**, image processing engine **478**, image registration engine **480**, procedure planning engine **482**, navigation engine **484**, and context analysis module **486**.

It is to be understood that the system is not intended to be limited to the components shown in the Figure. One or more components control and processing **400** may be provided as an external component or device. In one alternative embodiment, navigation module **484** may be provided as an external navigation system that is integrated with control and processing unit **400**.

Some embodiments may be implemented using processor **402** without additional instructions stored in memory **404**. Some embodiments may be implemented using the instructions stored in memory **404** for execution by one or more general purpose microprocessors. Thus, the disclosure is not limited to a specific configuration of hardware and/or software.

While some embodiments can be implemented in fully functioning computers and computer systems, various embodiments are capable of being distributed as a computing product in a variety of forms and are capable of being applied regardless of the particular type of machine or computer readable media used to actually effect the distribution.

At least some aspects disclosed can be embodied, at least in part, in software. That is, the techniques may be carried out in a computer system or other data processing system in response to its processor, such as a microprocessor, executing sequences of instructions contained in a memory, such as ROM, volatile RAM, non-volatile memory, cache or a remote storage device.

A computer readable storage medium can be used to store software and data which when executed by a data processing system causes the

system to perform various methods. The executable software and data may be stored in various places including for example ROM, volatile RAM, nonvolatile memory and/or cache. Portions of this software and/or data may be stored in any one of these storage devices.

The preceding example embodiments have described systems and methods in which a device is intraoperatively configured based on the identification of a medical instrument. In other example embodiments, one or more devices may be automatically controlled and/or configured by determining one or more context measures associated with a medical procedure. A "context measure", as used herein, refers to an identifier, data element, parameter or other form of information that pertains to the current state of a medical procedure. In one example, a context measure may describe, identify, or be associated with, the current phase or step of the medical procedure. In another example, a context measure may identify the medical procedure, or the type of medical procedure, that is being performed. In another example, a context measure may identify the presence of a tissue type during a medical procedure. In another example, a context measure may identify the presence of one or more fluids, such as biological fluids or non-biological fluids (e.g. wash fluids) during the medical procedure, and may further identify the type of fluid. Each of these examples relate to the image-based identification of information pertaining to the context of the medical procedure.

Examples of computer-readable storage media include, but are not limited to, recordable and non-recordable type media such as volatile and non-volatile memory devices, read only memory (ROM), random access

memory (RAM), flash memory devices, floppy and other removable disks, magnetic disk storage media, optical storage media (e.g., compact discs (CDs), digital versatile disks (DVDs), etc.), among others. The instructions can be embodied in digital and analog communication links for electrical, optical, acoustical or other forms of propagated signals, such as carrier waves, infrared signals, digital signals, and the like. The storage medium may be the internet cloud, or a computer readable storage medium such as a disc.

Furthermore, at least some of the methods described herein are capable of being distributed in a computer program product comprising a computer readable medium that bears computer usable instructions for execution by one or more processors, to perform aspects of the methods described. The medium may be provided in various forms such as, but not limited to, one or more diskettes, compact disks, tapes, chips, USB keys, external hard drives, wire-line transmissions, satellite transmissions, internet transmissions or downloads, magnetic and electronic storage media, digital and analog signals, and the like. The computer useable instructions may also be in various forms, including compiled and non-compiled code.

A purpose of the navigation system is to provide tools to the neurosurgeon that will lead to the most informed, least damaging neurosurgical operations. In addition to port-based removal of brain tumours and intracranial hemorrhages (ICH), the navigation system can also be applied to

- Brain biopsy
- Functional/Deep-Brain Stimulation
- Catheter/Shunt Placement

- Open Craniotomies
- Endonasal/Skull-based/ENT
- Spine procedures

Figure 11A is a flow chart illustrating alternate processing steps involved in a port based surgical procedure using a navigation system. In **Figure 11A**, the process initiates with operating room (OR) & Patient Setup (step **1102**). In step **1102**, necessary equipment such as lights, the navigation system and surgical tools are set up. The patient is then prepped and pinned in the headrest. The next step is registration (step **1104**) where the pose of the patient's head is determined relative to a base reference frame and the location of the base reference frame is correlated / registered to the imaging frame of reference.

The next step is to confirm the trajectory (step **1106**) where the port is positioned at the engagement point and the trajectory is displayed on the navigation system. The surgeon confirms that all equipment has sufficient line of sight and reach for the procedure. The surgeon then adjust the plan (step **1108**) where the surgeon creates a new engagement point and / or target point for surgery based on constraints observed in the operating room.

The next step involves pre-incision setup (step **1110**) where the patient and equipment are draped and the surgical site on the patient is shaved and sterilized. Thereafter, the registration and trajectory path is checked (step **1112**) to ensure that the equipment, navigation system and plan is accurate.

The next step in the procedure in **Figure 11A** is the approach (step **1114**) where a burr-hole craniotomy is created. A range of motion is tested with the port and intra-operative adjustment to trajectory is created if required. The dural opening is created and dural flap is stitched back. The port is then inserted down the trajectory via navigation guidance. Further a surgical camera is also positioned coaxially with the port.

Immediately after the approach (step **1114**) is the resection step (step **1116**) where the tumour is removed using a surgical tool such as the NICO Myriad® tool. The Port may be moved around within the constraints of the craniotomy by the surgeon during the procedure to cover all extents of the tumour or ICH. The surgical camera is re-positioned as required for viewing down ports. Further any bleeding is cauterized as required.

The next step involves reconstruction (step **1118**) where the surgical site is irrigated via the port. The port is then slowly retracted while viewing surgical site via the surgical camera. A graft is glued on, the dura is stitched back and the bone flap is replaced. Finally, the head clamp is removed. The last and final step is recovery (step **1120**) where the patient is sent to the recovery area in the hospital. If no hemorrhage occurs, the patient is sent home for recovery shortly after.

A navigation system can also be used for a brain biopsy. Brain Biopsy is the insertion of a thin needle into a patient's brain for purposes of removing a sample of brain tissue. The brain tissue is subsequently assessed by a pathologist to determine if it is cancerous. Brain Biopsy procedures can be conducted with or without a stereotactic frame. Both

types of procedures are performed using image-guidance but only frameless biopsies are conducted using a navigation system.

Figure 11B is a flow chart illustrating processing steps involved in a brain biopsy surgical procedure using a navigation system. The brain biopsy surgical procedure is very similar to a port-based surgical procedure (**Figure 11A**) with the exception of the biopsy (step **1122**), reconstruction (step **1124**) and recovery steps (step **1126**). In the biopsy step (step **1122**), a small hole is drilled into the skull at the engagement point. The biopsy needle is guided through the hole, into the brain and to the planned target. The biopsy needle is tracked in real-time and a biopsy sample is obtained and placed in a container for transportation to the pathology lab.

In **Figure 11B**, the reconstruction (step **1124**) and recovery steps (step **1126**) are much shorter for the brain biopsy procedures since the opening is much smaller. As noted above, the biopsy needle is also tracked continuously by the navigation system. In further embodiment, the surgeon holds the biopsy needle free-hand during the procedure. In other systems, a needle guide could be adhered to the skull, then positioned and oriented using the navigation system. If a depth-stop is included in this needle guide, the biopsy needle does not require continuous navigation.

Deep-Brain Stimulation (DBS) procedures implant a small electrode into a specific area of the brain for reduction of tremors from Parkinson's disease and dystonia. The electrode is connected to a control device implanted elsewhere in the body, typically near the clavicle. DBS can be conducted via a stereotactic frame or frameless. A navigation system may be contemplated for use with a frameless deep-brain stimulation procedure.

Figure 11C is a flow chart illustrating the processing steps involved in a deep-brain stimulation procedure using a navigation system. The workflow for deep-brain stimulation outlined in **Figure 11C** is similar to the brain biopsy procedure outline in **Figure 11B** with the differences of the latter steps of implanting electrode (step **1128**), placement confirmation (step **1130**) and implanting a control device (step **1132**).

During the implant electrode step (step **1128**), a small hole is drilled into the skull at the engagement point. A guidance device is positioned and oriented on the skull via the navigation system. And electrode lead is guided through the guidance device, into the brain and to the planned target. The electrode is also tracked in real-time with the navigation system. Thereafter, the workflow advances to the placement confirmation step (step **1130**) where confirmation of electrode placement is obtained by either listening to activity on the electrode, and / or by test stimulation of the area via the electrode and observing patient response.

After the placement confirmation step (step **1130**), the workflow proceeds to the implant control device step (step **1132**) where an incision is made in the location near the clavicle. A control device is inserted under the skin and attached to the clavicle. Electrodes leads are then routed under the skin from the electrode incision site to the control device. Thereafter, the process advances to the reconstruction (step **1118**) and recovery (step **1120**) steps as outlined in **Figure 11A**.

Catheter or shunt placement may also be assisted by a navigation system. Shunts or catheters are inserted into the brain cavity to treat patients with hydrocephalus. Cranial pressure is too great in these patients

as a result of excessive Cerebral Spinal Fluid (CSF). A shunt or catheter is introduced under image guidance and the excess CSF is drained into another part of the body where it will be reabsorbed.

Figure 11D is a flow chart illustrating the processing steps involved in a catheter / shunt placement procedure using a navigation system. This procedure is similar to the brain biopsy procedure in **Figure 11B** with the replacement of the biopsy step (step **1122**) with a shunt placement step (step **1134**). In a shunt placement step (step **1134**), a small hole is drilled into the skull at the engagement point. A guidance device is positioned and oriented on the skull via the navigation system. The shunt or catheter is guided through the guidance device, into the brain and to the planned target. The shunt or catheter is also tracked in real-time by the navigation system.

Update of Intraoperative Data

In an example embodiment of the Navigation system may update preoperative images (for example rendered 3D MRI image data) with intraoperatively acquired localized MRI images, using an MRI imaging probe (for example as described in copending International PCT Patent Publication WO 2014/138923 entitled **INSERTABLE IMAGING DEVICES AND METHODS OF USE THEREOF**). This can be accomplished by tracking the probe's location (i.e. spatial position and pose) relative to an anatomical part of a patient (this would be the brain for port based surgery) which has been registered with its corresponding 3D preoperative MRI. Once the probe is in a vicinity to image the anatomical part (such as a patients brain) the probe

actuates the MR scan. After the image is acquired the spatial position and pose of the imaging probe relative to the anatomical part, as determined by the tracking system, can be used to identify the location of the volume of the scan within the preoperative 3D image. The intraoperative image can then be registered with the preoperative image. Further low resolution or low quality portions of the preoperative image may be replaced by the localized intraoperative images.

In one embodiment, during a port-base procedure, brain displacement or deformation can be predicted with accurate simulation, using a priori tissue stiffness information, geometric knowledge of the introducer and port, a biomechanical model of tissue deformation, (using the skull as a boundary condition) and using pre-operative imaging data. This model can be updated using real-time imaging information as the introducer is positioned inside of the head, and more accurately if real-time imaging is performed using the in-situ port. For instance, real-time ultrasound imaging done on the tip of the port, can detect tissue stiffness inside the brain. This information can be used instead of the a-priori predicted stiffness, and can provide a better estimate of tissue movement. In addition, ultrasound can be used to identify sulci patterns as the port is being introduced. These sulci patterns can be matched to the pre-operative sulcus patterns, and a deformed pre-operative model can be generated based on this information.

In this iterative manner, the model will be updated by the system according to information obtained during the procedure to provide for accurate representations of the tumor location, for instance modeling of

tumor roll within the brain, and also the ability to measure the total stress and strain on nerve fibers as the port is inserted into the brain. This may be represented by the system as a global value and as with the weighting of the hierarchy of the fibers, the actual strain of the fibers may be used to calculate a value associated with the invasiveness of a surgical approach.

There may be a discrepancy between the pre-operative imaging data, and the real-time port information (US, OCT, photo acoustic, optical). This can be measured by matching sulcal patterns, blood vessel positions, or by quantifiable common contrast mechanisms such as elastic modulus, tissue anisotropy, blood-flow, etc. The real-time port information would be expected to represent the truth, and when there is a significant discrepancy, a scan would be done to update the volumetric MRI and/or CT scans to update the pre or intraoperative scanning volume. In the optimal configuration, an MRI port coil would be used in conjunction with an external MRI system to acquire a 3D volume demonstrating sulci path, tumor, nerve fascicles by way of DTI acquisition, and blood vessels. As the acquisition time is typically much longer than US, OCT or photo-acoustic imaging, it is not expected to be used as a real-time modality, however it can be effectively utilized as a single modality to position the access port with pseudo-real time capability (typically not faster than 1fps). Future availability of faster acquisition technologies may provide a near real-time DTI information using a port coil.

While the Applicant's teachings described herein are in conjunction with various embodiments for illustrative purposes, it is not intended that the applicant's teachings be limited to such embodiments. On the contrary, the

applicant's teachings described and illustrated herein encompass various alternatives, modifications, and equivalents, without departing from the embodiments, the general scope of which is defined in the appended claims.

Except to the extent necessary or inherent in the processes themselves, no particular order to steps or stages of methods or processes described in this disclosure is intended or implied. In many cases the order of process steps may be varied without changing the purpose, effect, or import of the methods described.

WHAT IS CLAIMED IS:

1. A navigation system to support a medical procedure, comprising:
 - a navigation module configured for controlling trajectory and visual display of one or more medical instruments, said navigation module having a power supply, a processor control module programmed with navigation control software, a storage device connected to said processor control module, said storage device having stored therein a surgical trajectory path plan to be followed on an anatomical part undergoing the medical procedure;
 - said one or more medical instruments including at least one uniquely identifiable tracking marker associated therewith,
 - a virtual representation of said one or more medical instruments stored in said storage device with its associated at least one uniquely identifiable tracking marker, said virtual representation of said one or more medical instruments being geometrically accurate with respect to size and shape of the medical instrument;
 - a virtual representation of one or more tissue structures of interest of the anatomical part from said surgical trajectory path plan stored in said storage device;
 - a tracking system in communication with said navigation module for tracking said one or more medical instruments using said at least one uniquely identifiable tracking marker;
 - said processor control module programmed with instructions to
 - compare the tracked one or more medical instruments with said geometrically accurate virtual representation of said one or more medical instruments stored in said storage device for identifying the one or more medical instruments in use, and

match the virtual representation of the tissue structures with an actual view of the tissue structure of interest;

at least one display for displaying

a surgical path defined by the surgical trajectory path plan, preoperative imaging data of the anatomical part undergoing the medical procedure which is registered with the anatomical part, said one or more medical instruments used in the medical procedure, the virtual representation of one or more tissue structures from said surgical trajectory path plan, and the matched virtual representation of the tissue structures with the actual view of the tissue of interest; and

said navigation module including a guidance mechanism to visually assist a surgeon to translate one of the one or more medical instruments, being tracked by said tracking system, along the surgical path.

2. The system according to claim 1 including at least one imaging device configured to acquire intraoperative imaging data of a localized region within the anatomical part during the medical procedure, said at least one imaging device including at least one uniquely identifiable tracking marker associated therewith which is tracked by said tracking system, and wherein the navigation module is programmed with instructions to use the intraoperative imaging data of said localized region to update the preoperative imaging data of said localized region within the anatomical part during the medical procedure based on positional information of the tracked imaging device relative to the anatomical part.

3. The system according to claim 2 wherein said preoperative imaging data are acquired using MRI, and wherein said imaging device is an insertable MRI device adapted to be inserted into the anatomical part, and wherein the navigation module is programmed to adaptively update a section of the MRI acquired preoperative imaging data using localized intraoperative MRI imaging data acquired using said insertable MRI device.
4. The system according to claim 2 or 3 wherein the navigation module is programmed to provide positionally accurate maps correlating intraoperative imaging data acquired during the medical procedure to locations where the intraoperative imaging data was acquired in the anatomical part.
5. The system according to claim 4 wherein the navigation module is programmed to represent the positionally accurate maps by spatially correlated color maps.
6. The system according to claim 2, 3, 4 or 5 wherein the navigation module is programmed to enable quantitative registration in which an absolute quantitative metric is measured intraoperatively and use that measured absolute quantitative metric to register imaging data obtained using one or more imaging modalities.
7. The system according to claim 6 wherein the absolute quantitative metric includes any one or combination of MRI (T1), MRI (T2), cell density, tissue density, tissue anisotropy, tissue stiffness, fluid flow per volume or area, electrical conductivity, pH, and pressure.

8. The system according to any one of claims 2 to 7 wherein the navigation module is programmed with instructions to compute biomechanical properties of tissue being imaged by said at least one imaging device, and to use said computed biomechanical properties to update a tissue model of the anatomical part undergoing the medical procedure.
9. The system according to any one of claims 2 to 8 wherein the navigation module is programmed with instructions to analyze tissue patterns from the intraoperative imaging data acquired by said at least one imaging device and form a comparison between them and the preoperative imaging data, and based on said comparison, generating a deformed preoperative model of the anatomical part.
10. The system according to any one of claims 2 to 9 wherein said imaging device is any one of an ultrasound imaging device, an optical coherence tomography imaging device, a photo acoustic imaging device and an optical imaging device.
11. The system according to any one of claims 2 to 10 wherein said at least one imaging device is configured for imaging tissue structures, and wherein the navigation module is programmed with instructions to use the intraoperative imaging data of imaged tissue structures to update the preoperative imaging data of the tissue structures.
12. The system according to any one of claims 2 to 11 wherein the anatomical part undergoing the medical procedure is a patient's brain, and wherein the medical procedure is a port based surgery utilizing a port and introducer, and wherein the

surgical path is a multi-segment surgical path defined by a multi-segment surgical trajectory path plan.

13. The system according to claim 12 wherein said at least one imaging device is configured for imaging tissue structures of the brain, including brain fiber tracts, sulci structures, nerve fascicles, and blood vessels.

14. The system according to any one of claims 2 to 13 wherein the navigation module is programmed with instructions for comparing the preoperative imaging data and the intraoperative imaging data and detecting for discrepancy between the preoperative imaging data, and the intraoperative imaging data, and upon detecting discrepancies, performing a scan to update volumetric and/or CT scans to update preoperative scanning volumes or intraoperative scanning volumes.

15. The system according to claim 14 wherein the navigation module is programmed for comparing and detecting for discrepancies between the preoperative imaging data and the intraoperative imaging data by matching any one or combination of sulcal patterns, blood vessel positions, and by quantifiable common contrast mechanisms including elastic modulus, tissue anisotropy, and blood-flow.

16. The system according to any one of claims 1 to 15 wherein the navigation module is programmed to visually display preoperative imaging data, intraoperative imaging data, a superposition of the preoperative and intraoperative imaging data, the surgical path defined by the surgical trajectory path plan in both the preoperative

and intraoperative imaging data, an actual surgical path calculated by the navigation module based on the intraoperative imaging data, and a superposition of the surgical path defined by the surgical plan and the actual surgical path.

17. The system according to claim 16 wherein the navigation module is programmed to calculate and display a course change from the actual surgical path back to the surgical path defined by the surgical trajectory path plan consistent with a surgical outcome criteria associated with the surgical trajectory path plan with respect to regions of the anatomical part to be avoided or approached.

18. A navigation system to support a medical procedure on a patient, comprising:
a navigation module configured for controlling trajectory and visual display of one or more medical instruments, said navigation module having a power supply, a processor control module programmed with navigation control software, a storage device connected to said processor control module;

said storage device having stored therein a surgical trajectory path plan to be followed on an anatomical part undergoing the medical procedure and preoperative imaging data of the anatomical part of the patient undergoing the medical procedure;

each of said one or more medical instruments including at least one uniquely identifiable tracking marker associated therewith,

a virtual representation of said one or more medical instruments stored in said storage device with its associated at least one uniquely identifiable tracking marker, said virtual representation of said one or more medical instruments being geometrically accurate with respect to size and shape of the medical instrument;

a virtual representation of one or more tissue structures from said surgical trajectory path plan stored in said storage device;

a tracking camera in communication with said navigation module for tracking said one or more medical instruments using said at least one uniquely identifiable tracking marker and associated virtual representation relative to said registered anatomical part;

said processor control module programmed with instructions for

comparing the tracked one or more medical instruments with said geometrically accurate virtual representation of said one or more medical instruments stored in said storage device for identifying the one or more medical instruments in use,

matching the virtual representation of the tissue structures with an actual view of the tissue structure of interest;

at least one display for displaying

a surgical path defined by the surgical trajectory path plan,
the preoperative imaging data of the anatomical part undergoing the medical procedure which is registered with the anatomical part,
said one or more medical instruments used in the medical procedure,
said virtual representation of one or more tissue structures from said surgical trajectory path plan, and
the matched virtual representation of the tissue structures with the actual view of the tissue of interest;

an imaging device configured to acquire intraoperative imaging data of a localized region within the anatomical part, said imaging device including at least one

uniquely identifiable tracking marker associated therewith which is tracked by said tracking camera; and

the navigation module being programmed with instructions to use the intraoperative imaging data of said localized region to update the preoperative imaging data of said localized region within the anatomical part during the medical procedure based on positional information of the tracked imaging device relative to the anatomical part.

19. The system according to claim 18 wherein said preoperative imaging data are acquired using MRI, and wherein said imaging device is an insertable MRI device adapted to be inserted into the anatomical part, and wherein the navigation module is programmed to adaptively update a section of the MRI acquired preoperative imaging data using localized intraoperative MRI imaging data acquired using said insertable MRI device.

20. The system according to claim 18 or 19 wherein the navigation module is programmed to provide positionally accurate maps correlating intra-operative information acquired during the medical procedure to locations where the information were acquired in the anatomical part.

21. The system according to claim 20 wherein the navigation module is programmed to represent the positionally accurate maps by spatially correlated color maps.

22. The system according to claim 18, 19, 20 or 21 wherein the navigation module is programmed to enable quantitative registration in which an absolute quantitative metric is measured intraoperatively and use that measured absolute quantitative metric to register imaging data obtained using one or more imaging modalities.
23. The system according to claim 22 wherein the absolute quantitative metric includes any one or combination of MRI (T1), MRI (T2), cell density, tissue density, tissue anisotropy, tissue stiffness, fluid flow per volume or area, electrical conductivity, pH, and pressure.
24. The system according to any one of claims 18 to 23 wherein the navigation module is programmed with instructions to compute biomechanical properties of tissue being imaged by said at least one imaging device, and to use said computed biomechanical properties to update a tissue model of the anatomical part undergoing the medical procedure.
25. The system according to any one of claims 18 to 24 wherein the navigation module is programmed with instructions to analyze tissue patterns from the intraoperative imaging data acquired by said at least one imaging device and form a comparison between them and the preoperative imaging data, and based on said comparison, generating a deformed pre-operative model of the anatomical part.

26. The system according to any one of claims 18 to 25 wherein said imaging device is any one of an ultrasound imaging device, an optical coherence tomography imaging device, a photo acoustic imaging device and an optical imaging device.

27. The system according to any one of claims 18 to 26 wherein said at least one imaging device is configured for imaging tissue structures, and wherein the navigation module is programmed with instructions to use the intraoperative imaging data of imaged tissue structures to update the preoperative imaging data of the tissue structures.

28. The system according to any one of claims 18 to 27 wherein the anatomical part undergoing the medical procedure is a patient's brain, and wherein the medical procedure is a port based surgery utilizing a port and introducer, and wherein the surgical path is a multi-segment surgical path defined by a multi-segment surgical trajectory path plan.

29. The system according to claim 28 wherein said at least one imaging device is configured for imaging tissue structures of the brain, including brain fiber tracts, sulci structures, nerve fascicles, and blood vessels.

30. The system according to any one of claims 18 to 29 wherein the navigation module is programmed with instructions for comparing the preoperative imaging data and the intraoperative imaging data and detecting for discrepancy between the preoperative imaging data, and the intraoperative imaging data, and upon detecting

discrepancies, performing a scan to update volumetric and/or CT scans to update preoperative scanning volumes or intraoperative scanning volumes.

31. The system according to claim 30 wherein the navigation module is programmed for comparing and detecting for discrepancies between the preoperative imaging data and the intraoperative imaging data by matching any one or combination of sulci patterns, blood vessel positions, and by quantifiable common contrast mechanisms including elastic modulus, tissue anisotropy, and blood-flow.

32. The system according to any one of claims 18 to 31 wherein the navigation module is programmed to visually display pre-operative imaging data, intra-operative imaging data, a superposition of the preoperative and intraoperative imaging data, the surgical path defined by the surgical plan in both the preoperative and intraoperative imaging data, an actual surgical path calculated by the navigation module based on the intraoperative imaging data, and a superposition of the surgical path defined by the surgical plan and the actual surgical path.

33. The system according to claim 32 wherein the navigation module is programmed to calculate and display a course change from the actual surgical path back to the surgical path defined by the surgical plan consistent with the a surgical outcome criteria associated with the surgical plan with respect to regions of the anatomical part to be avoided or approached.

34. The system according to claim 1 wherein said one or more tissue structures from said surgical trajectory path plan is any one or combination of fiber tracts, sulci structures, nerve fascicles, and blood vessels.

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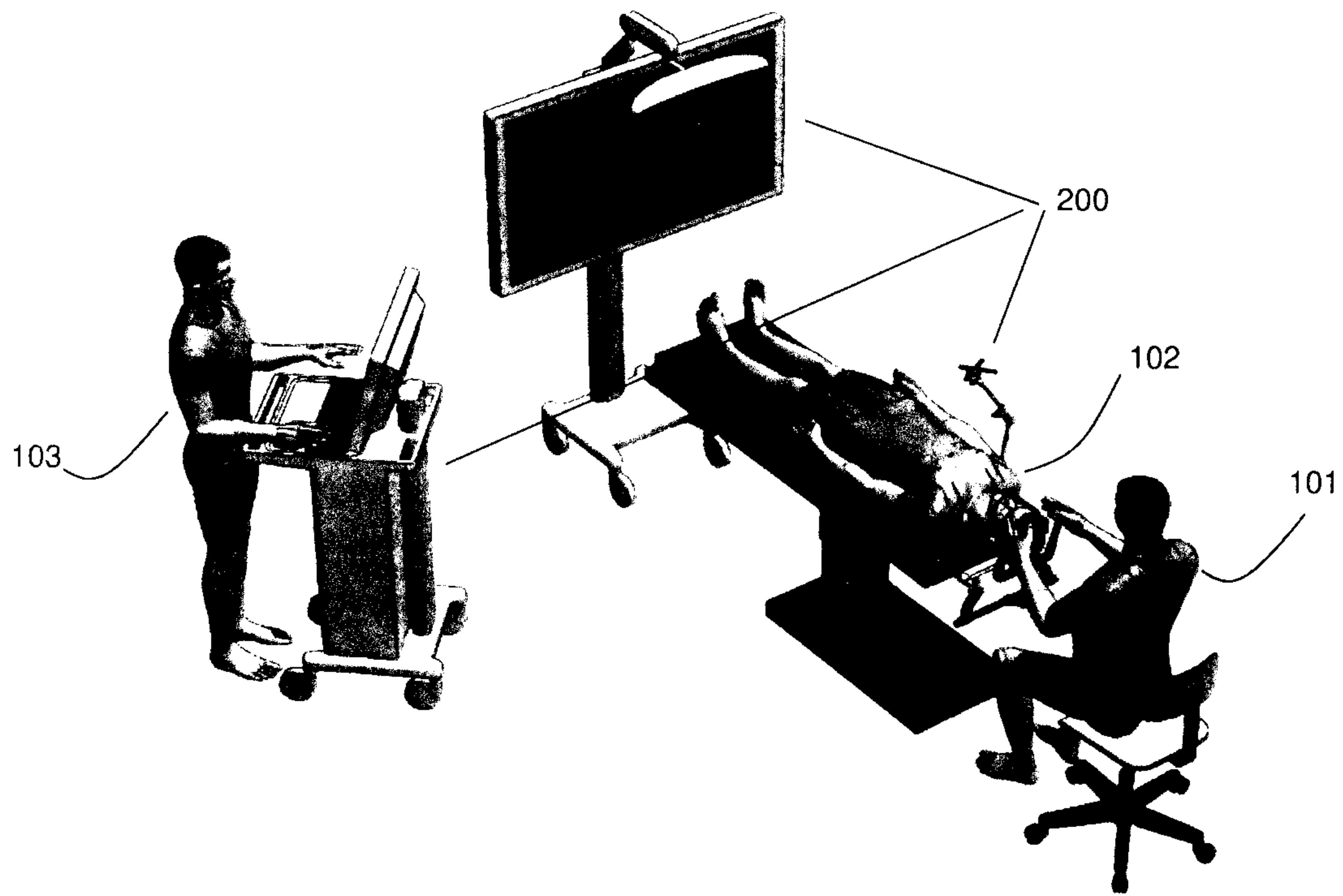


Figure 1

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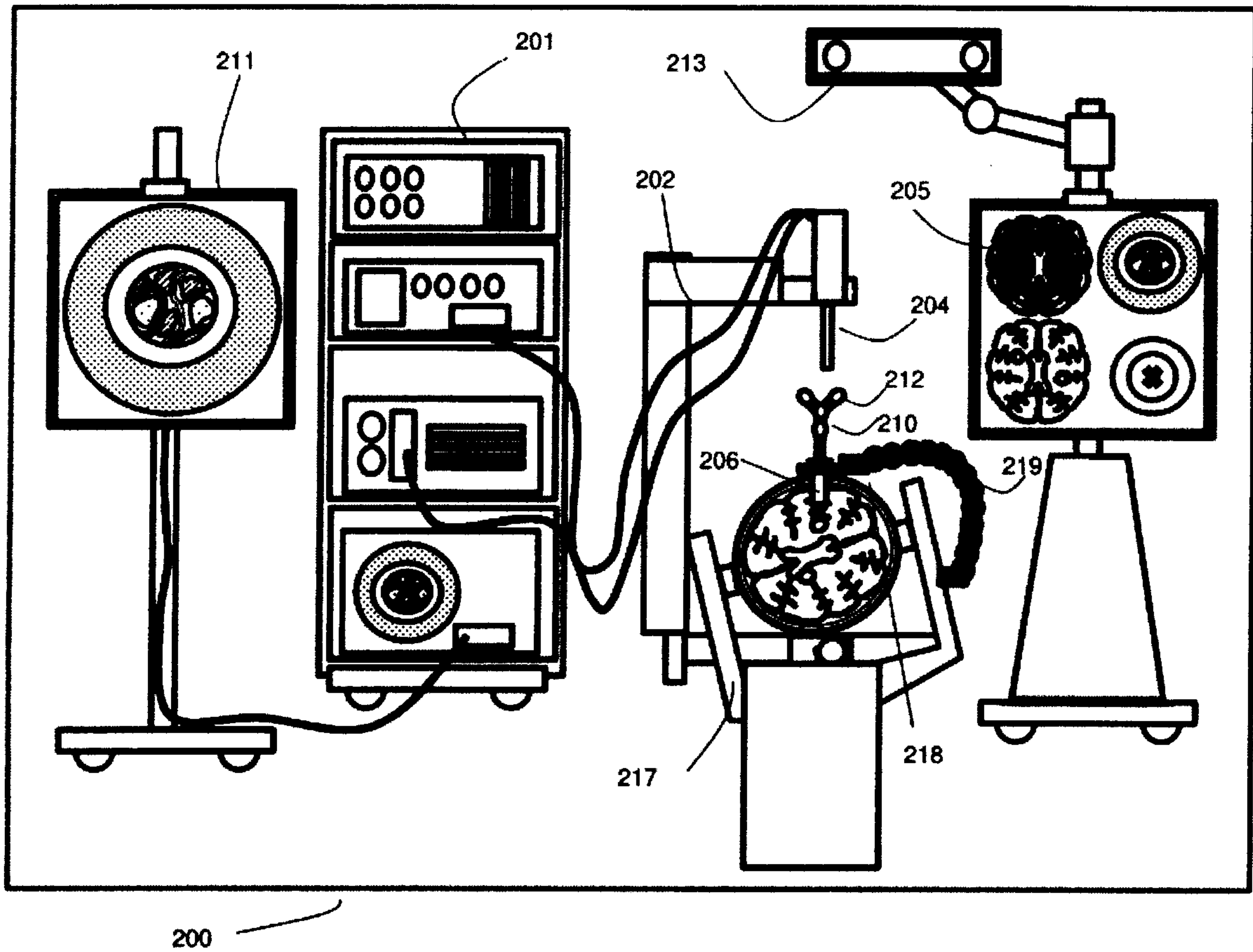


Figure 2

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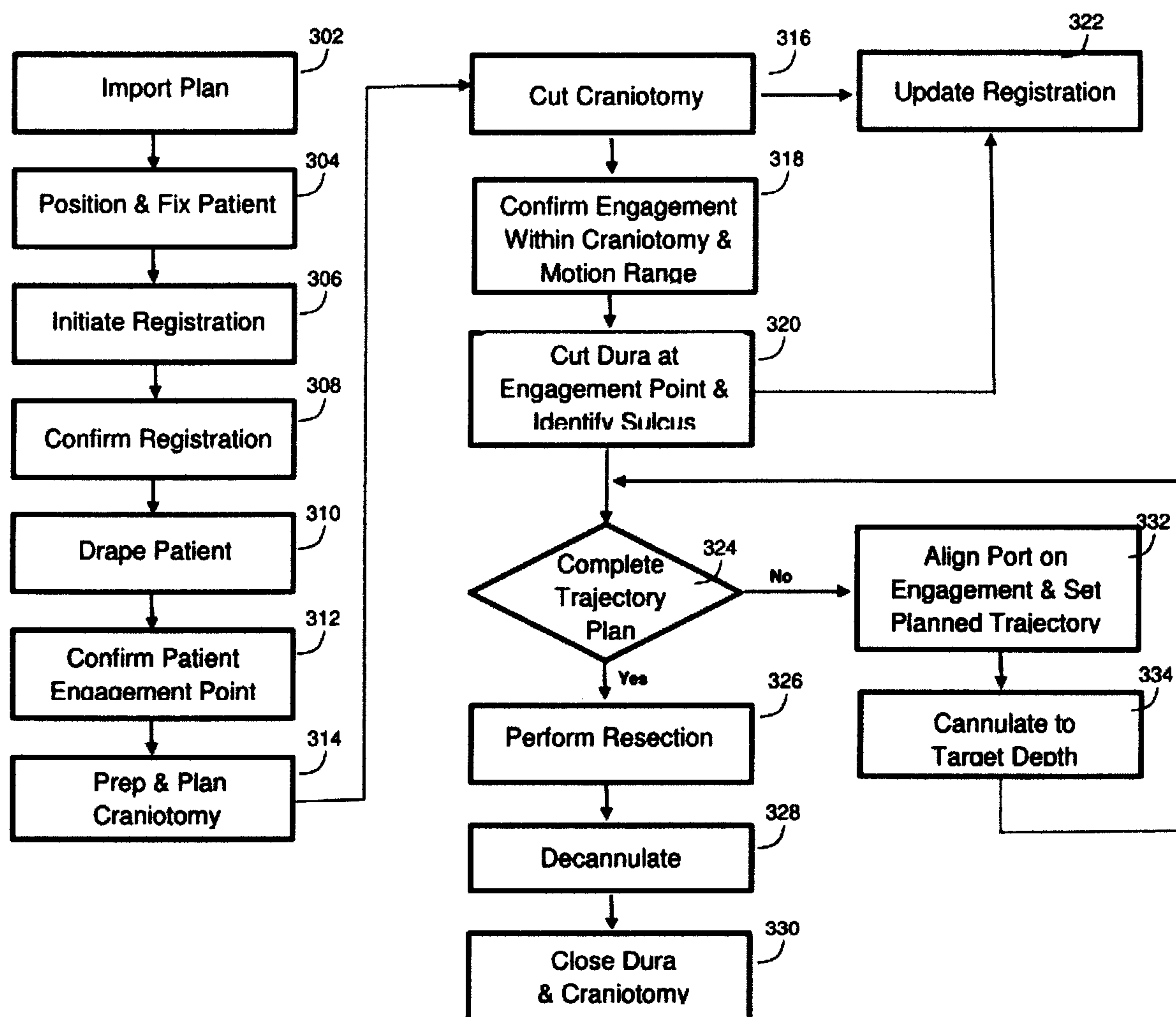


Figure 3A

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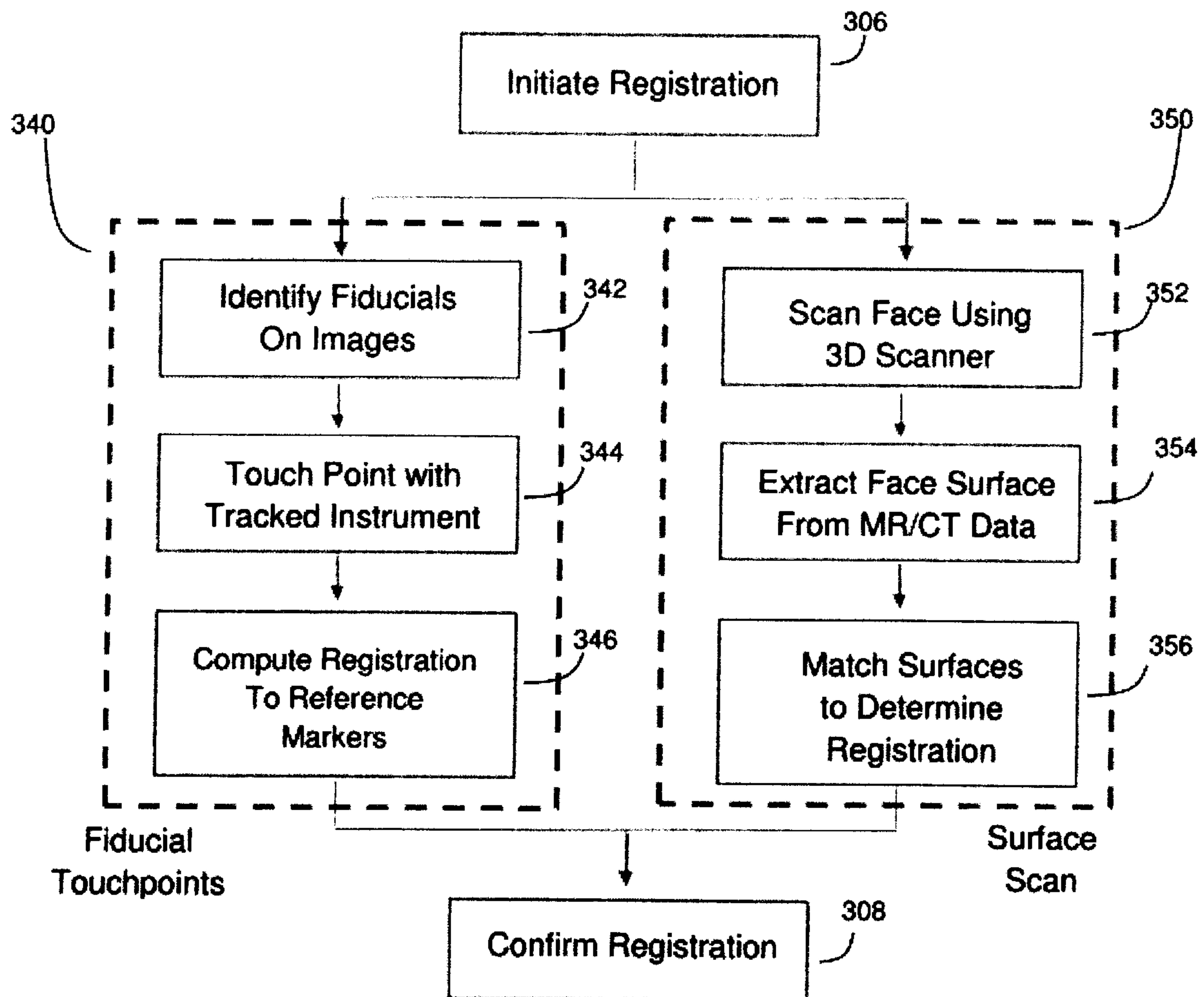


Figure 3B

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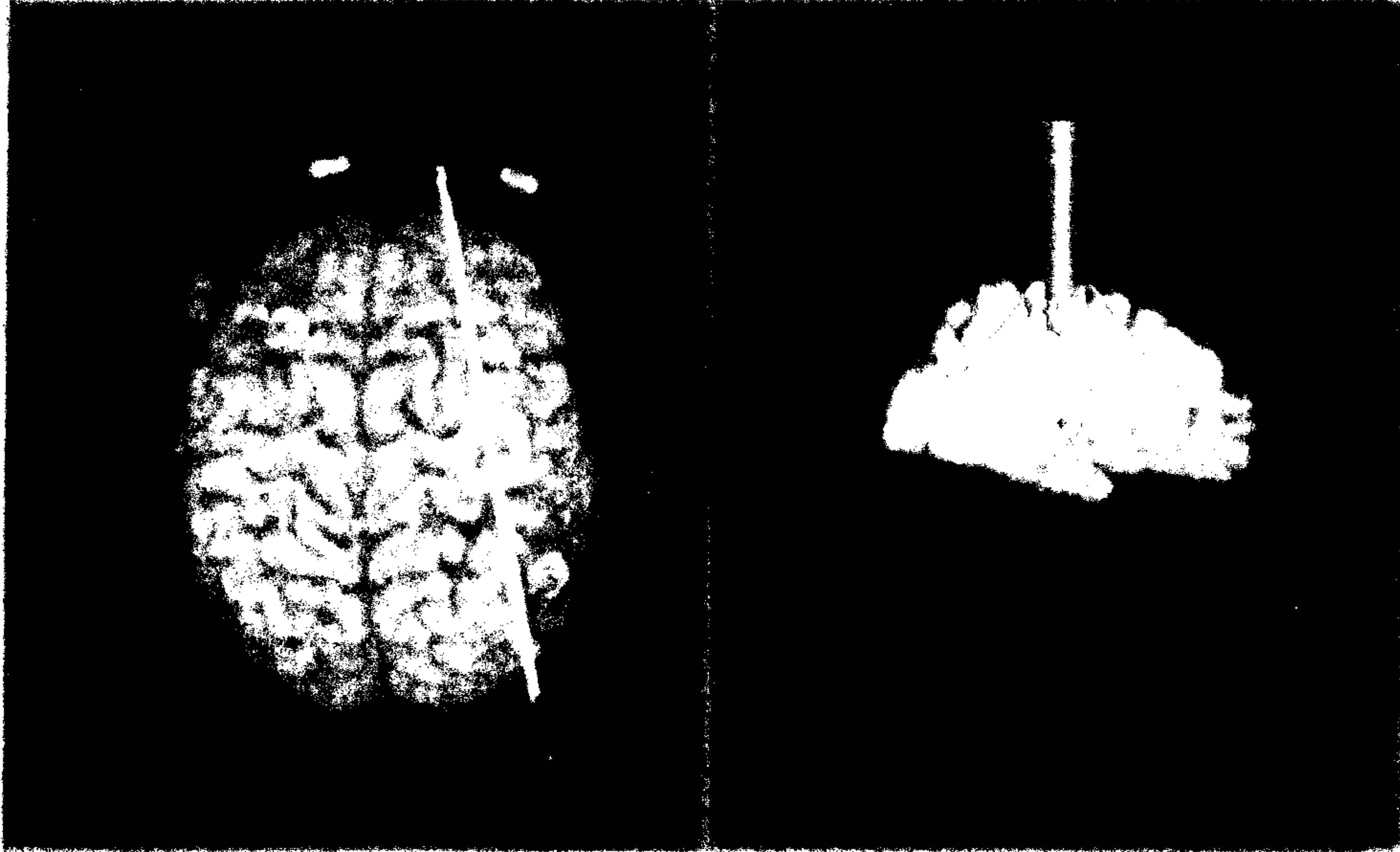


Figure 4A

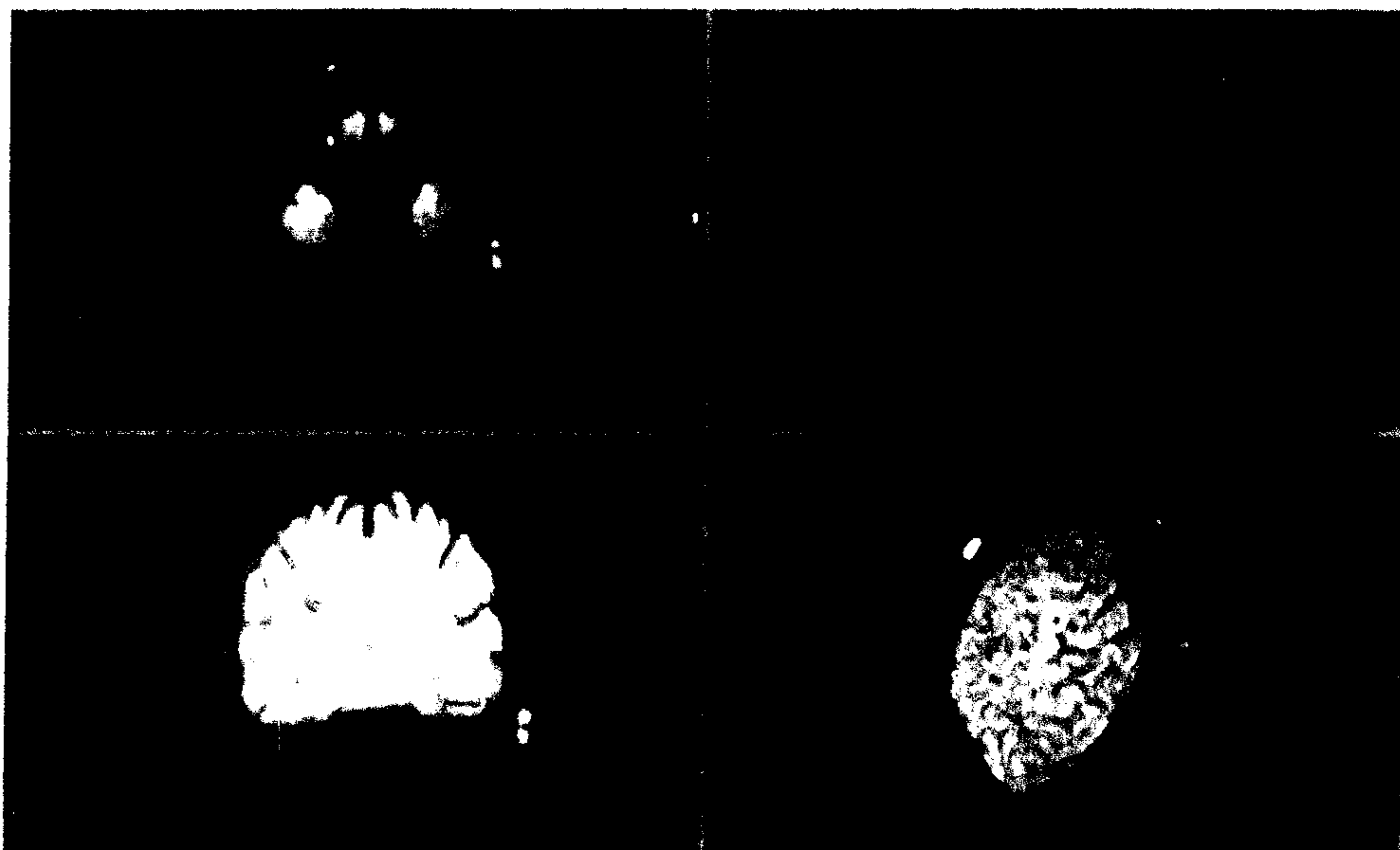


Figure 4B

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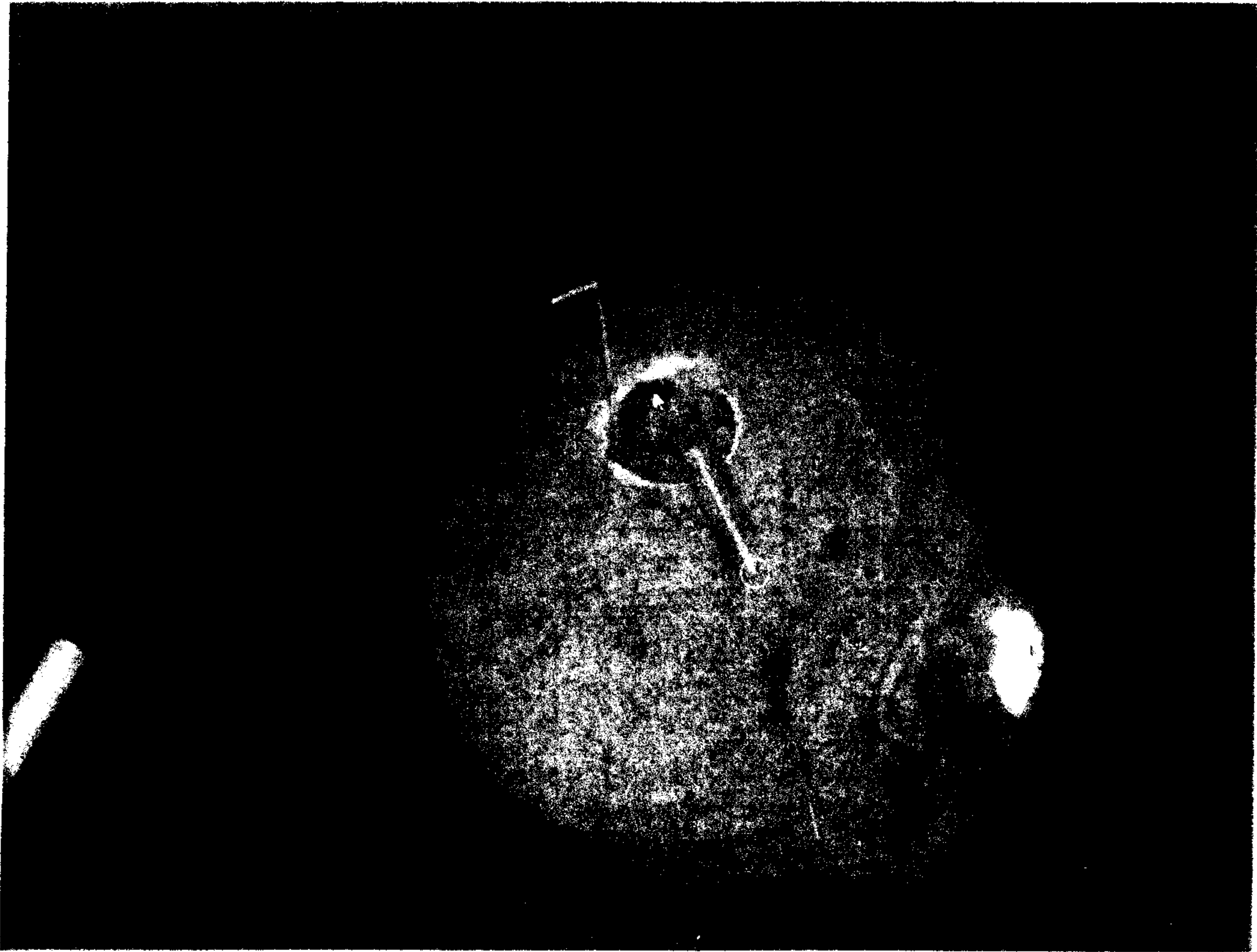


Figure 4C

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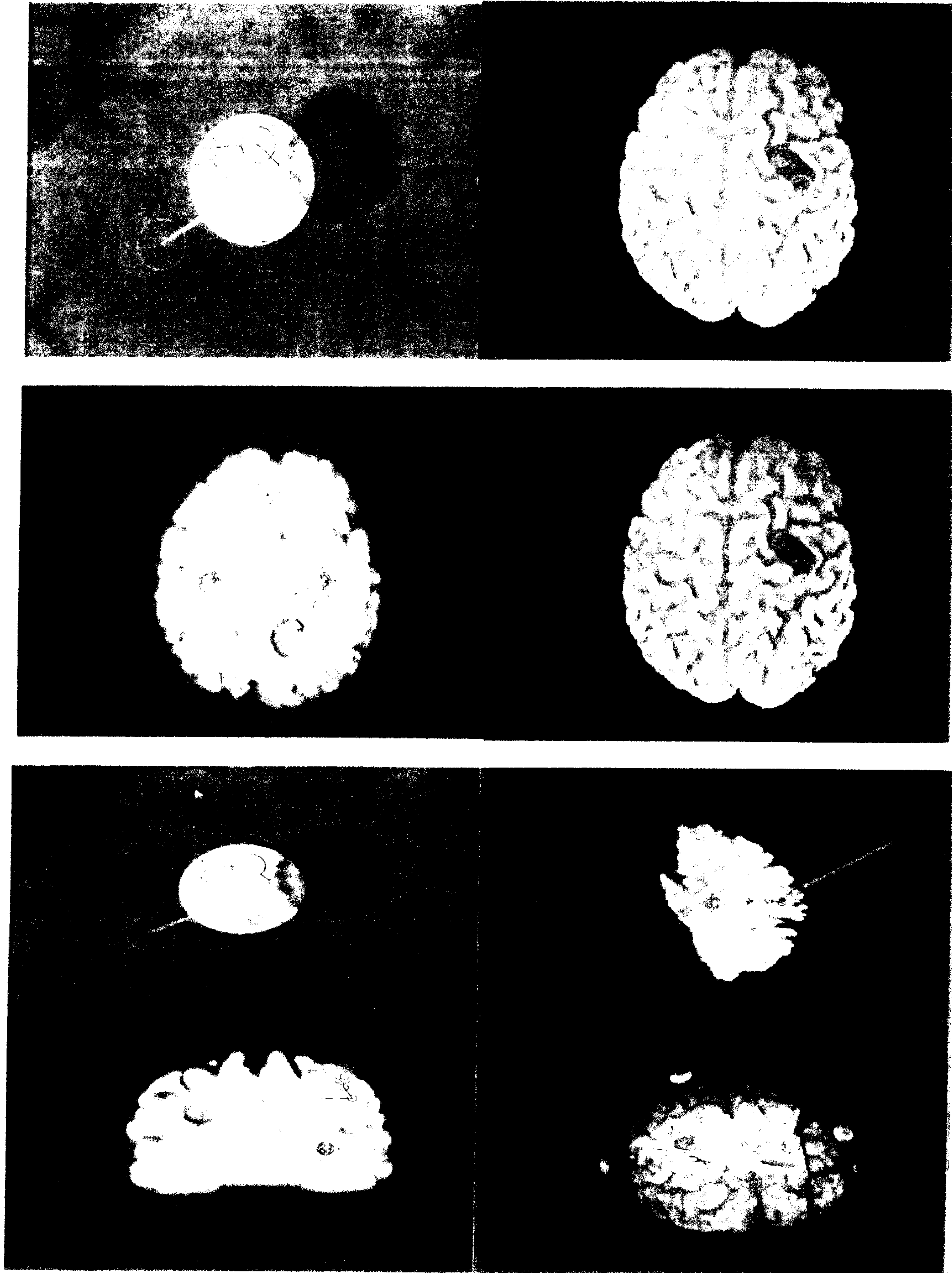


Figure 4D

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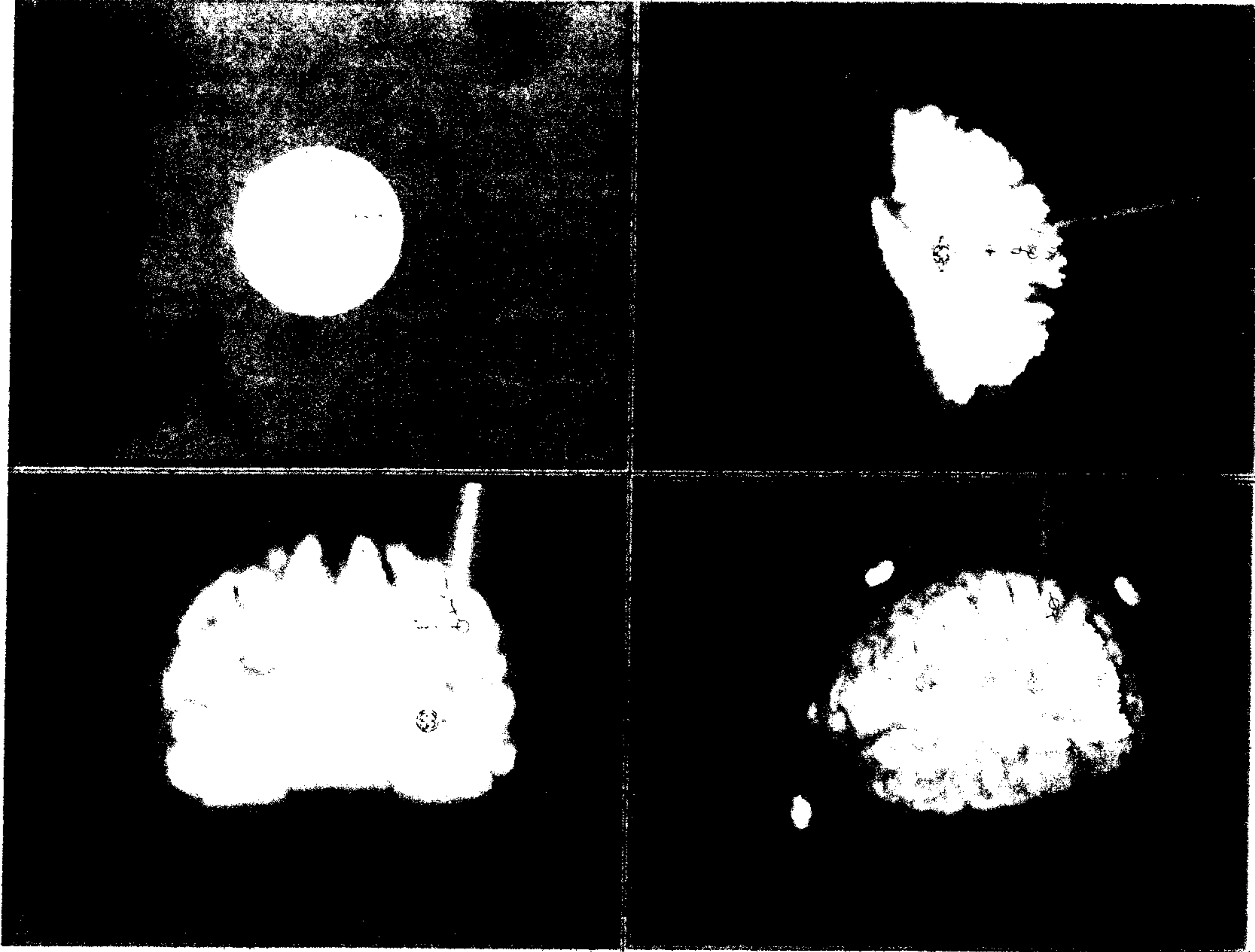


Figure 4E

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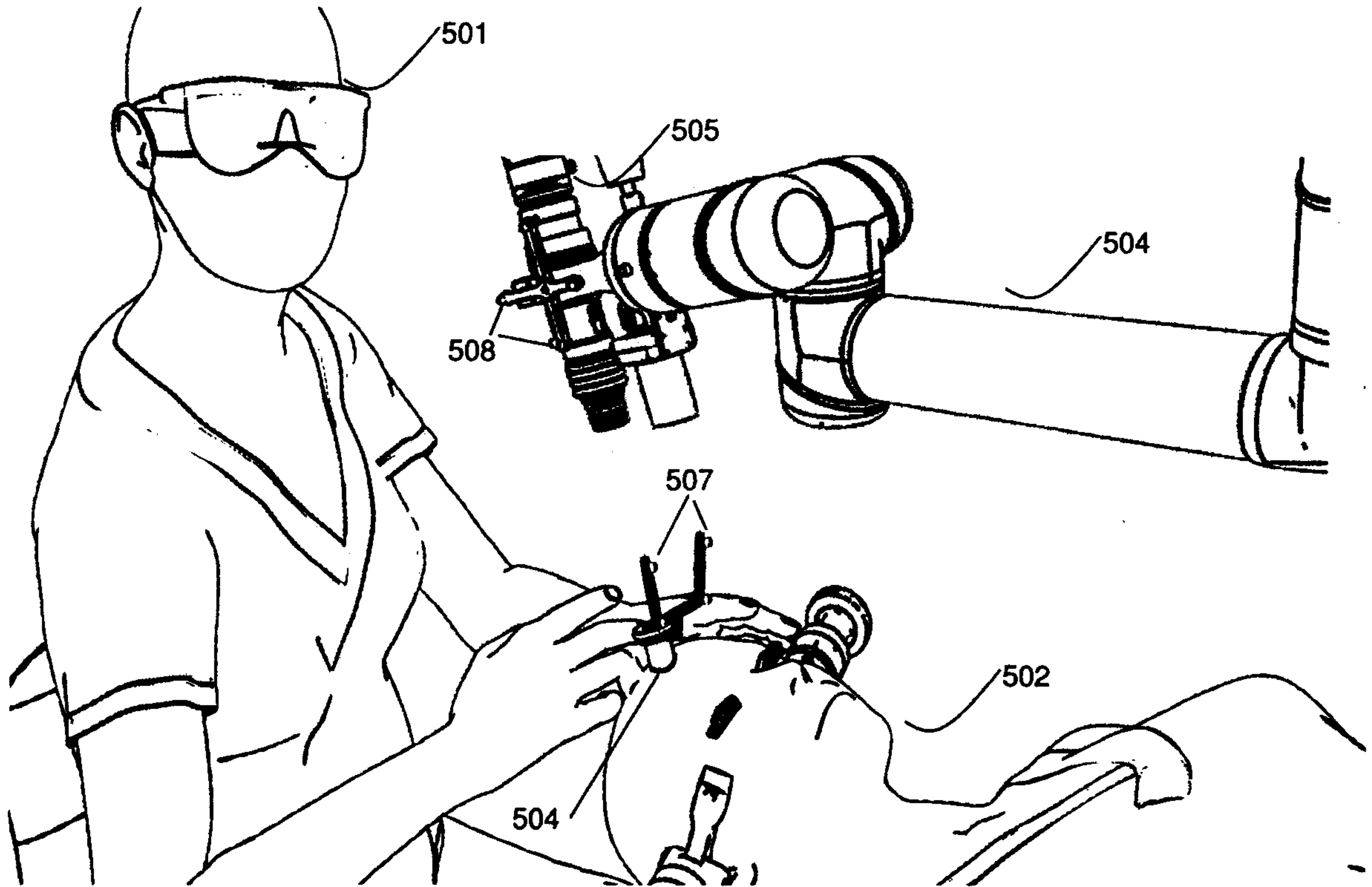
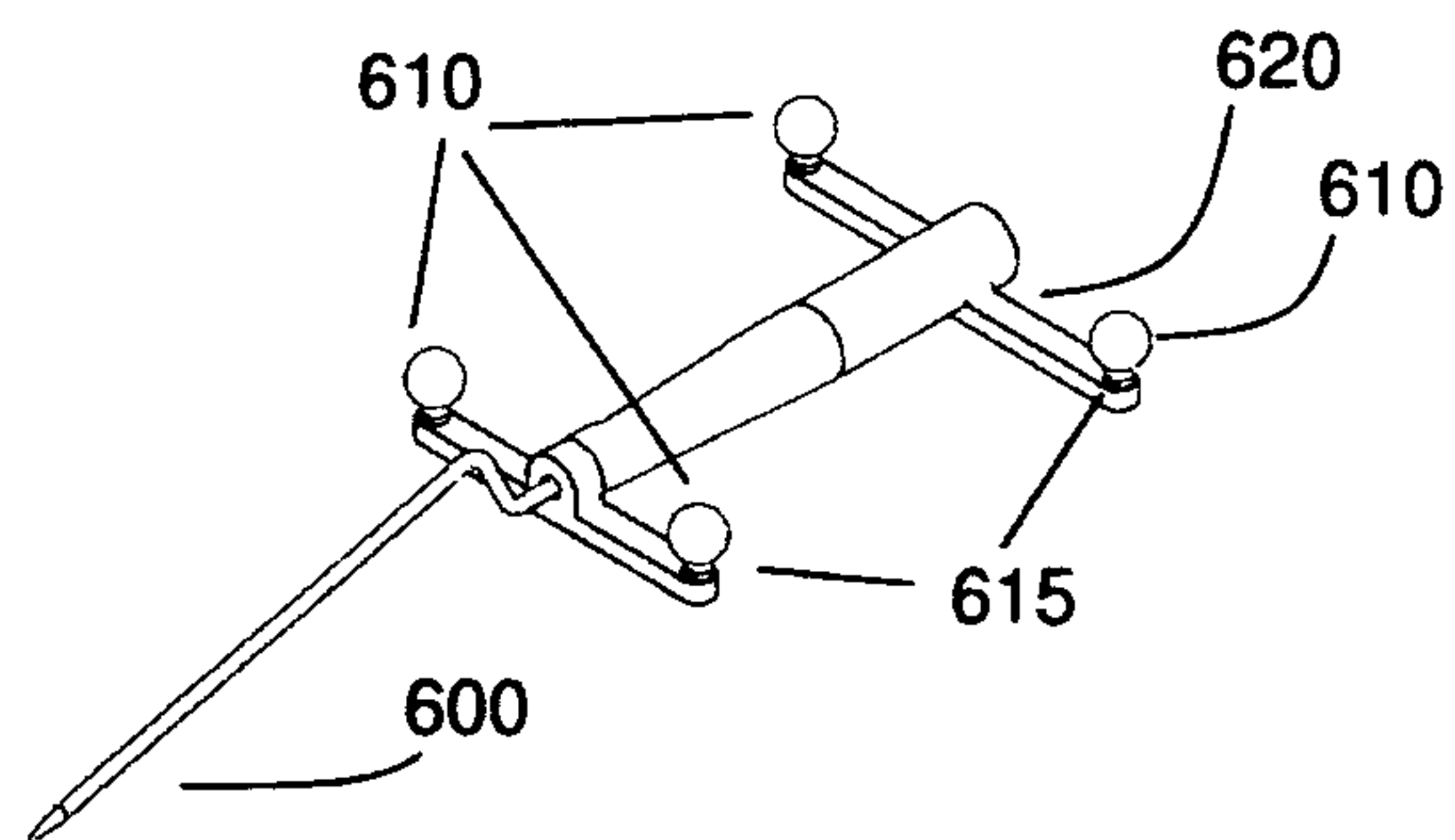
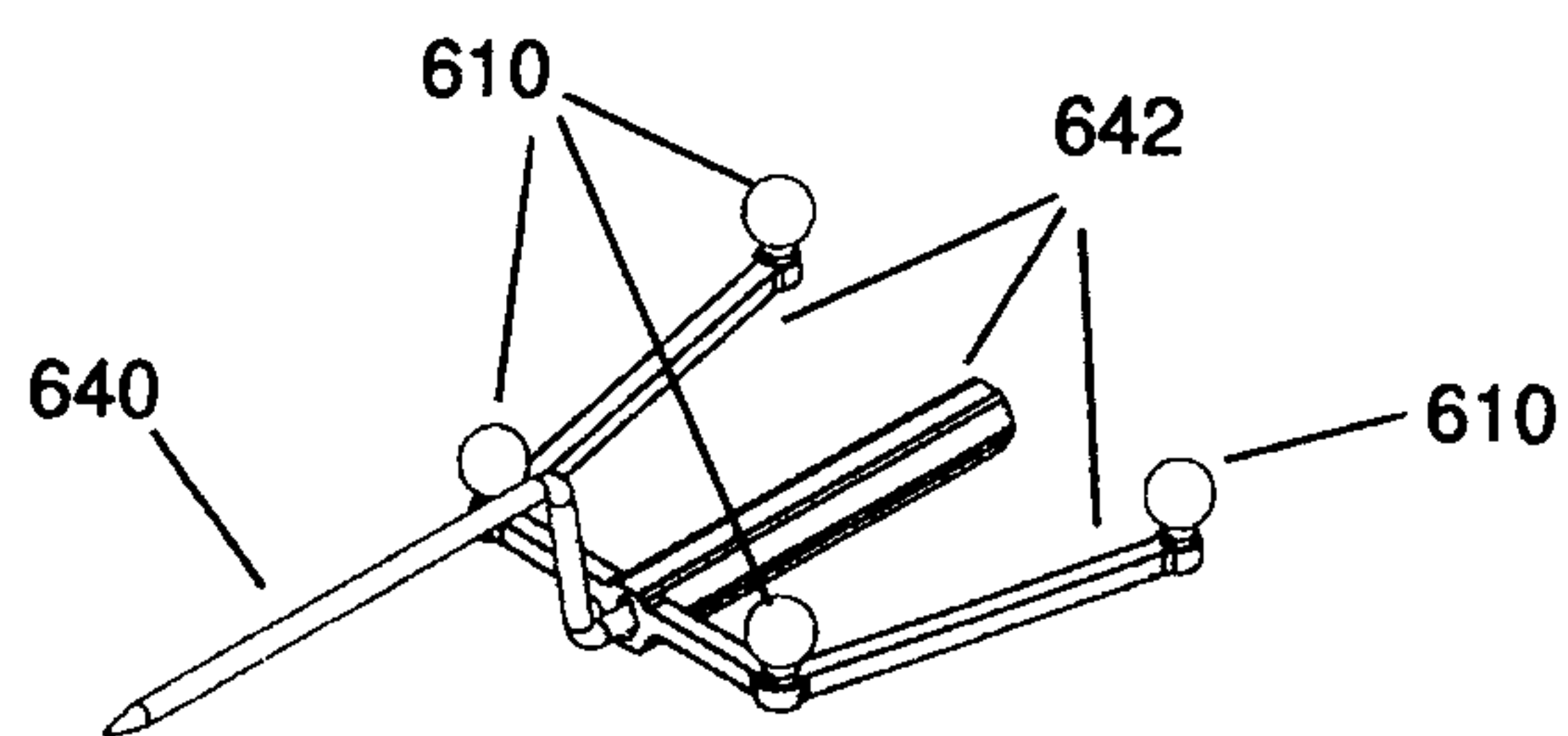
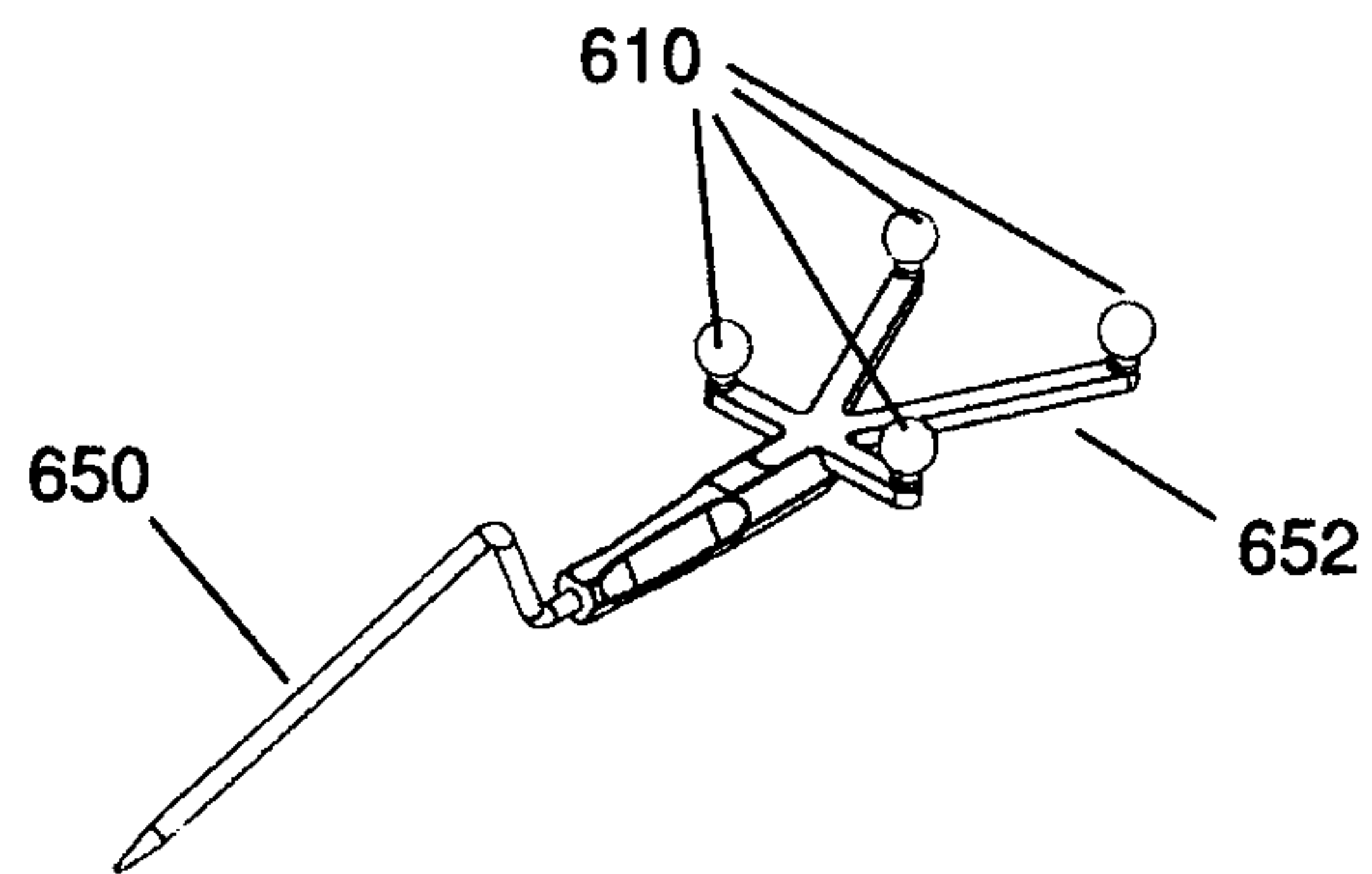
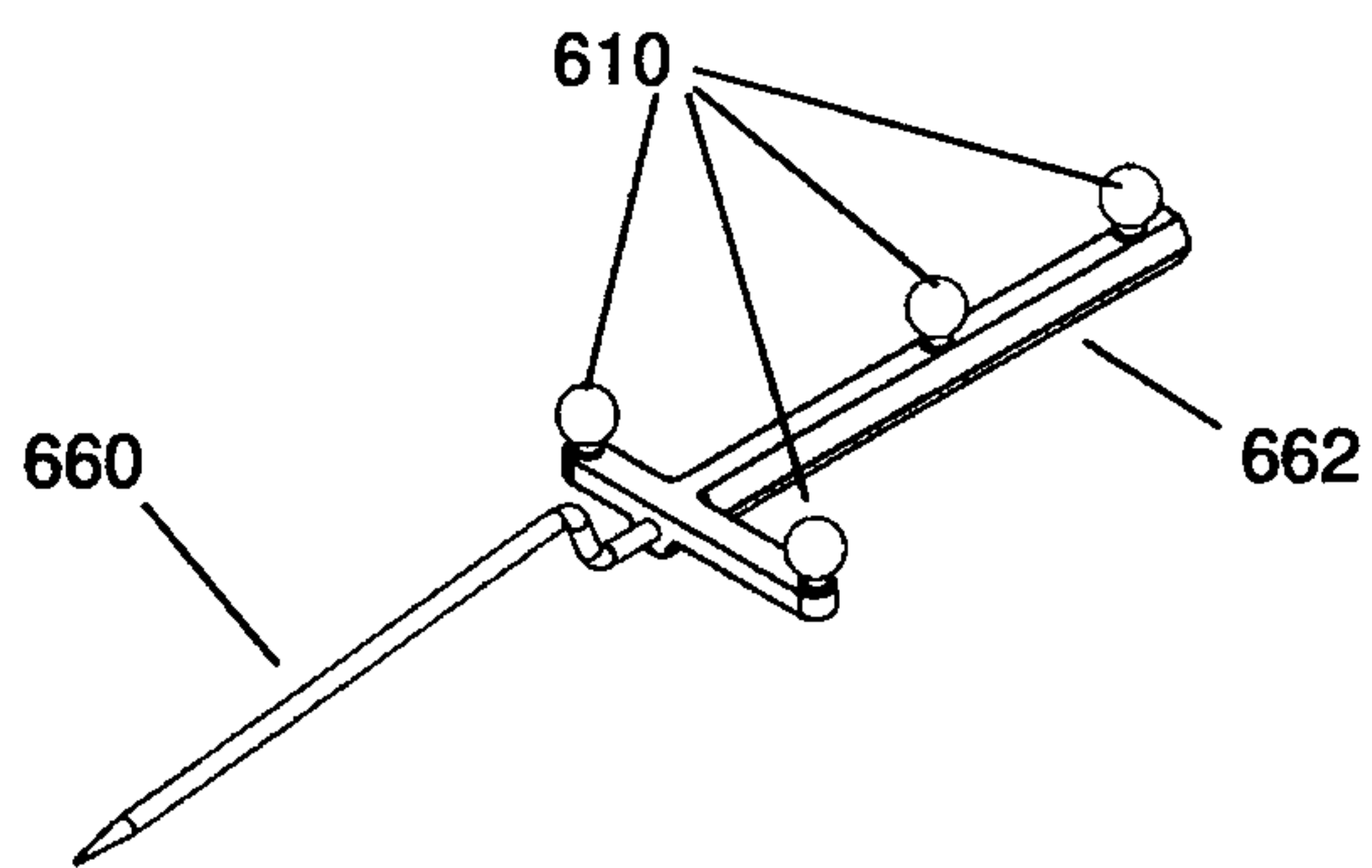


Figure 5

10/20**Figure 6A****Figure 6B**

11/20**Figure 6C****Figure 6D**

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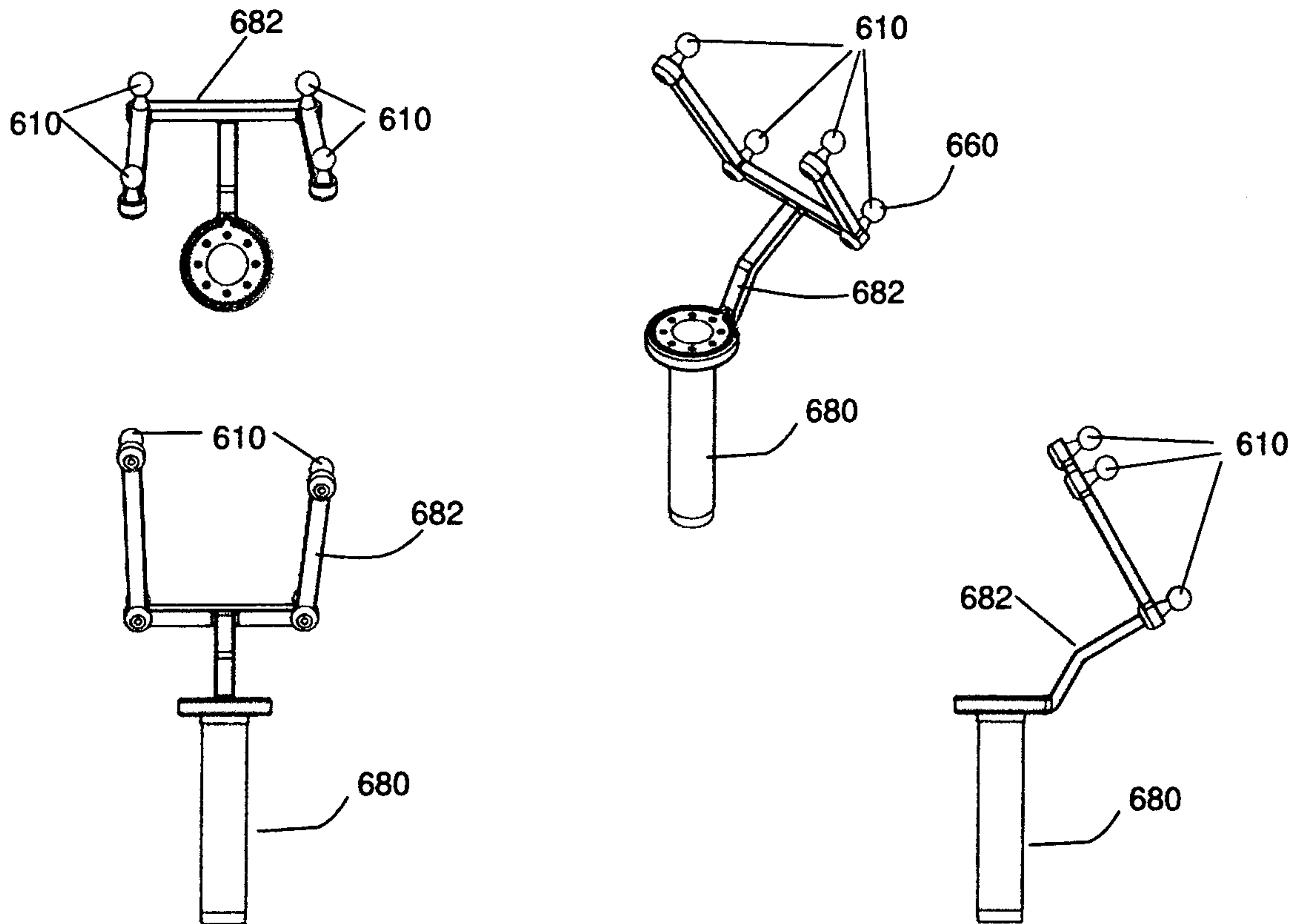
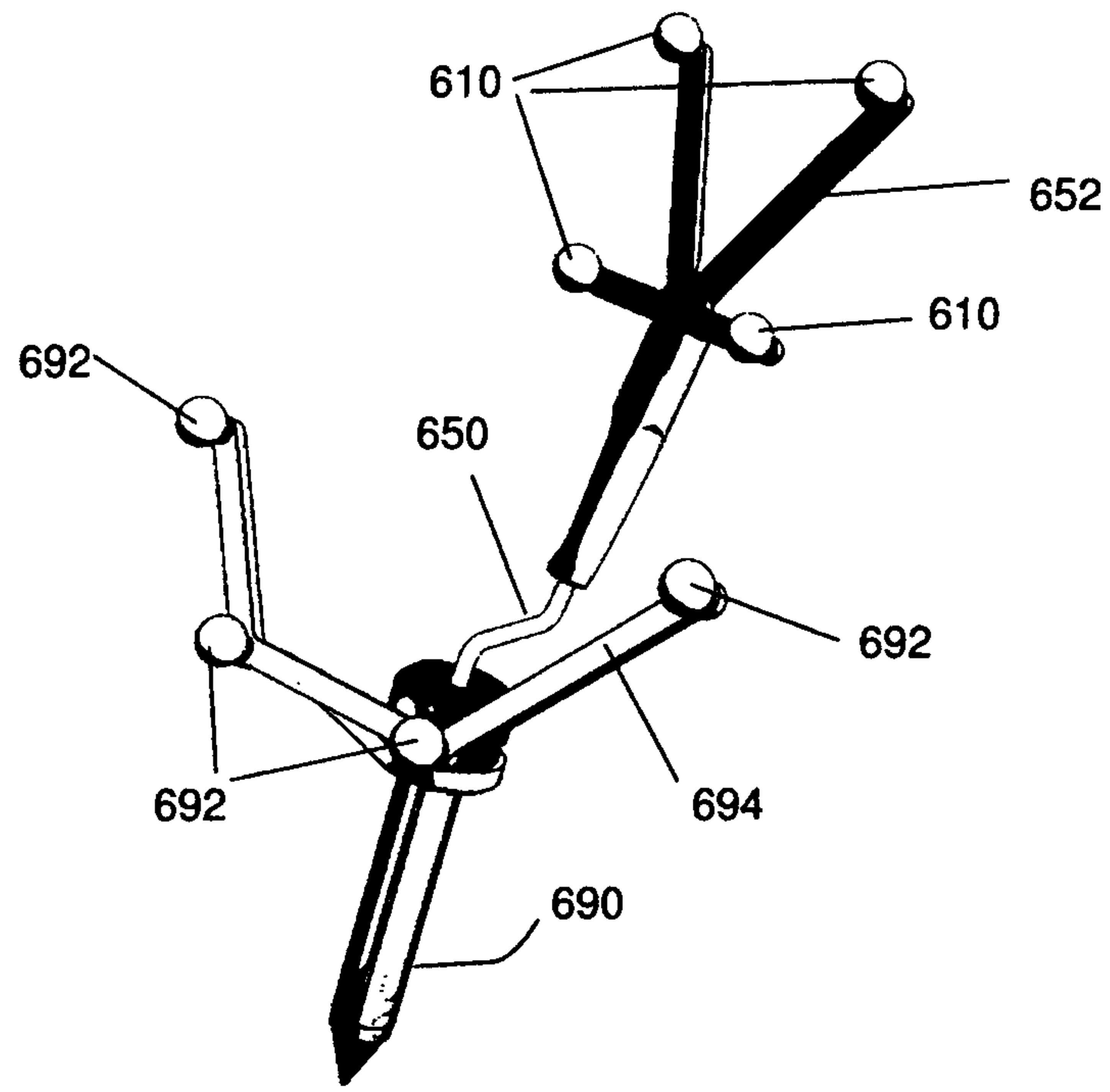


Figure 6E

13/20**Figure 7**

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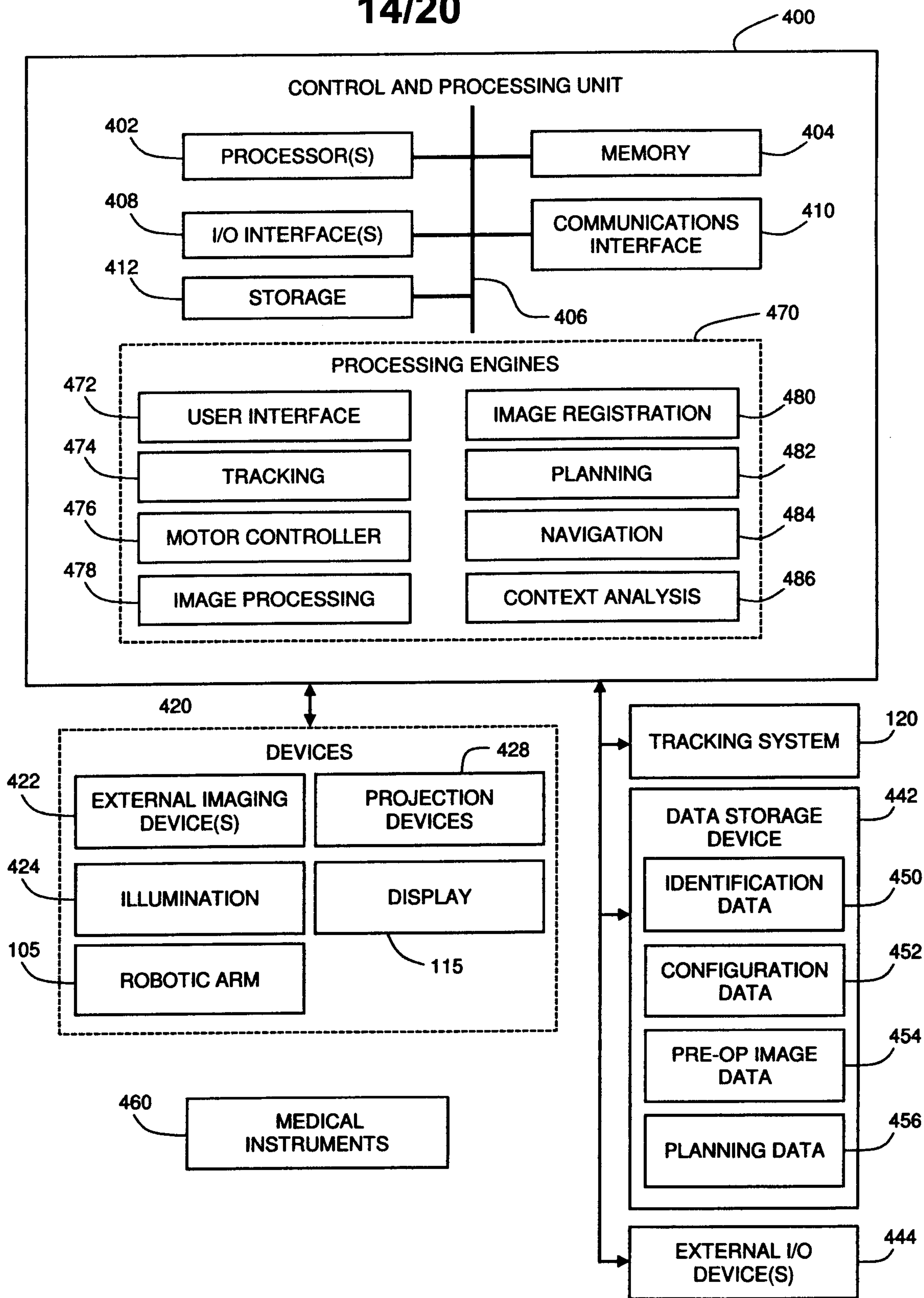


Figure 8

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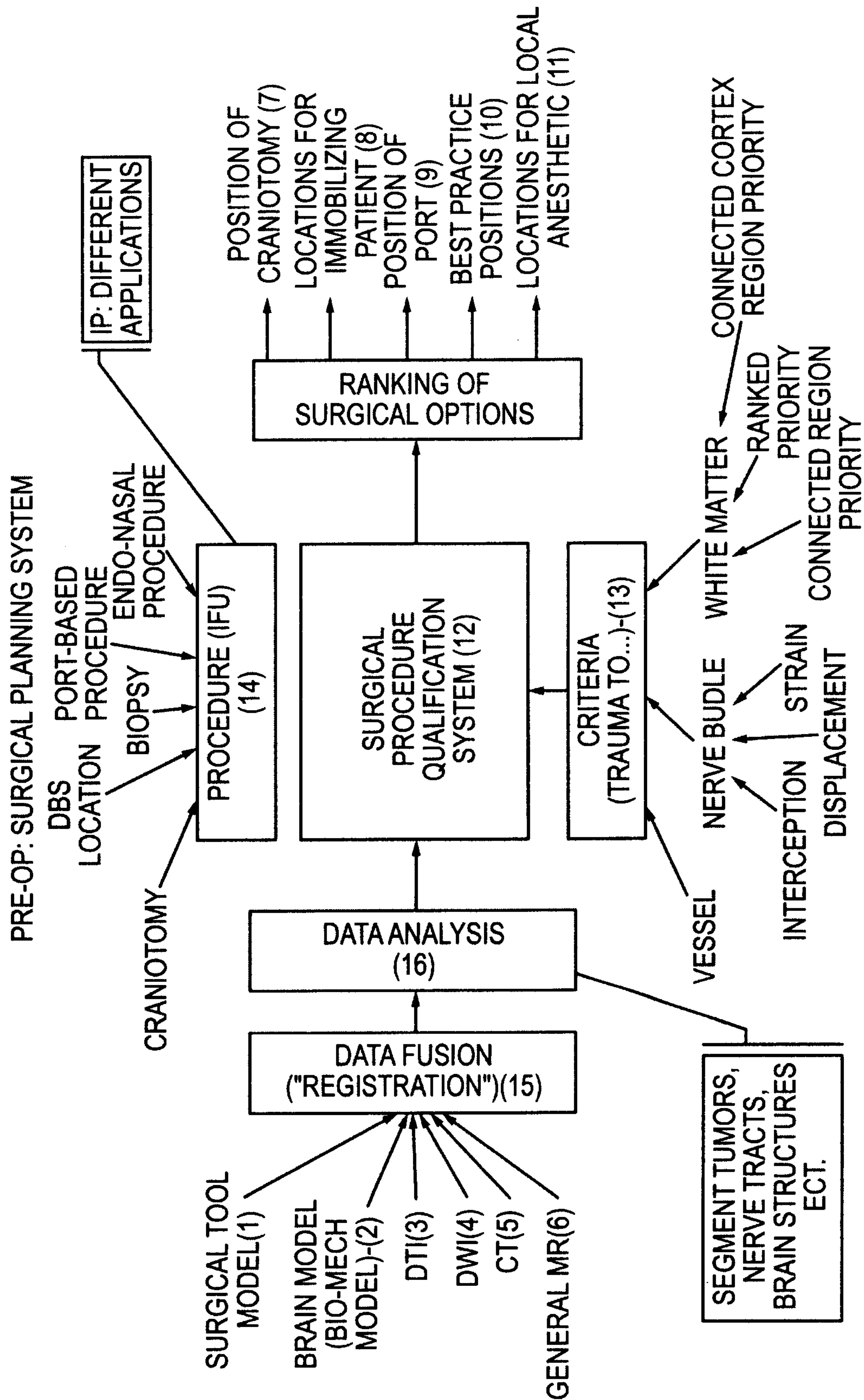
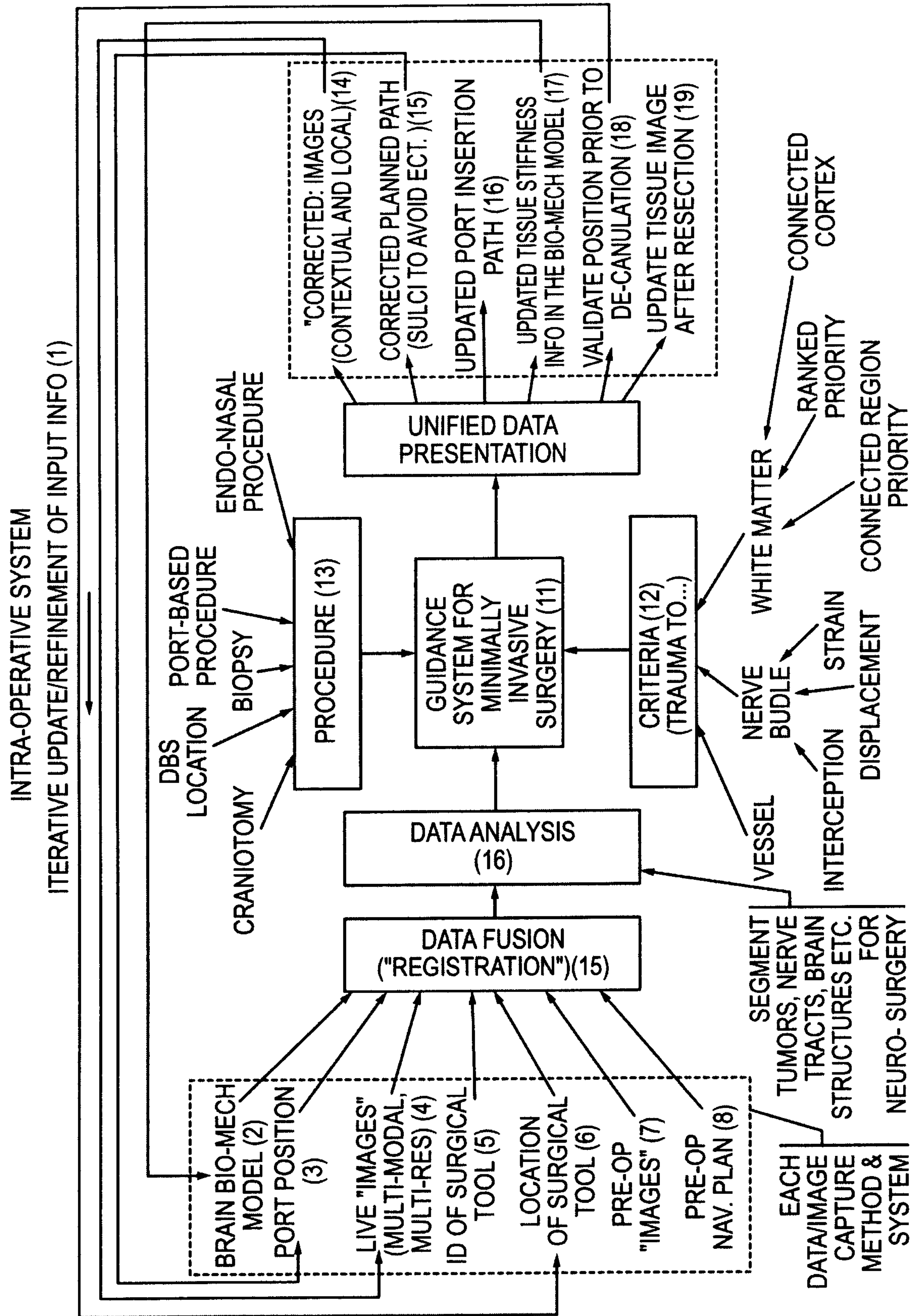
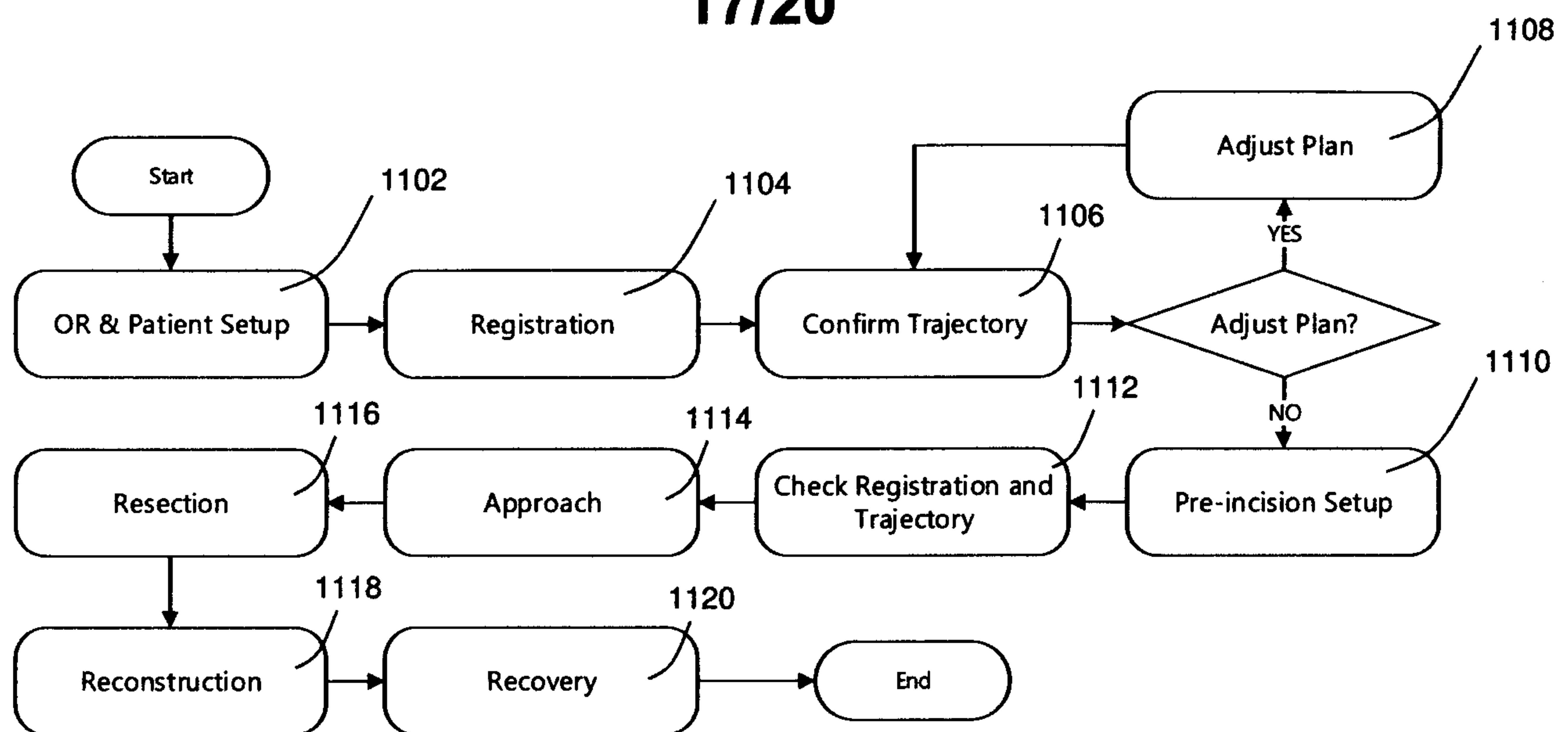


Figure 9

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17/20**Figure 11A: Alternate Workflow steps in port-based procedure**

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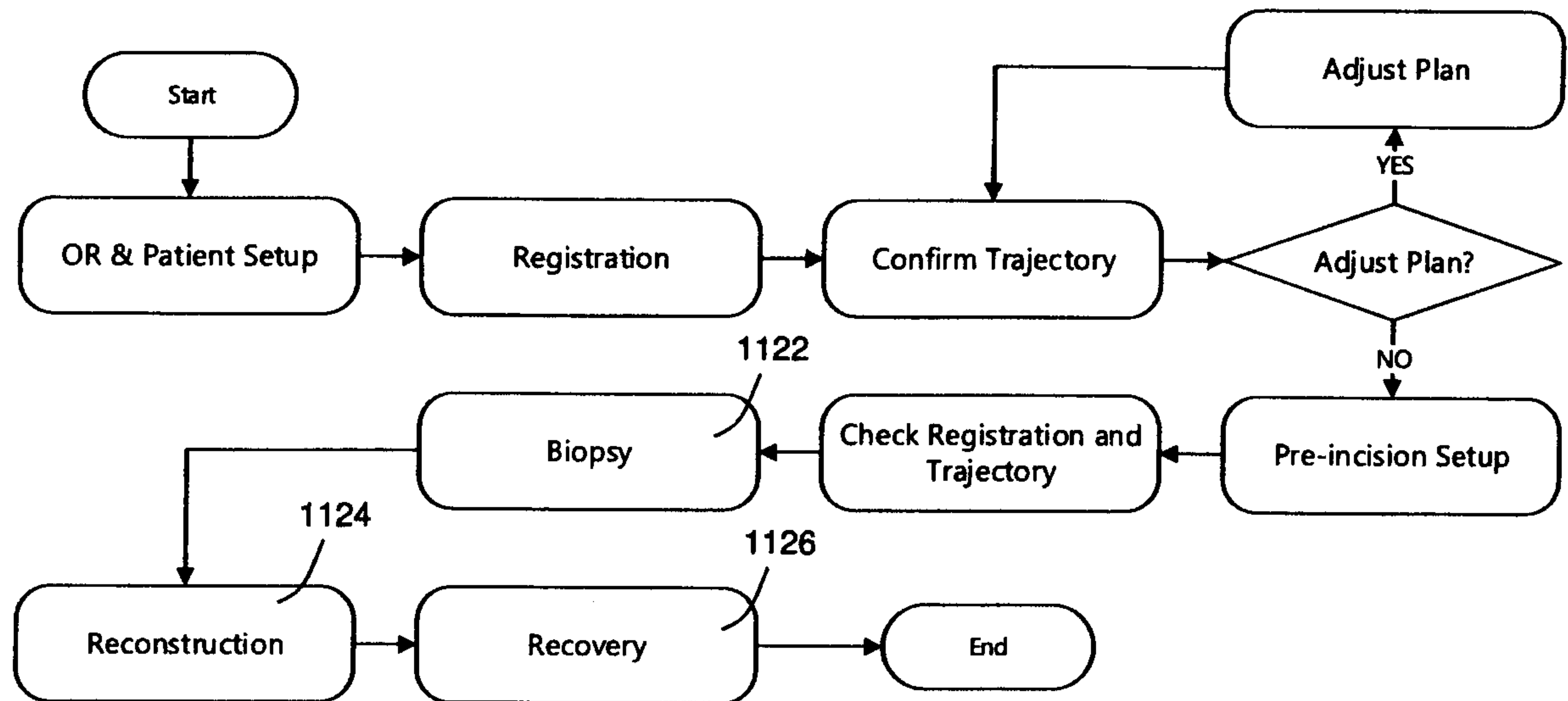
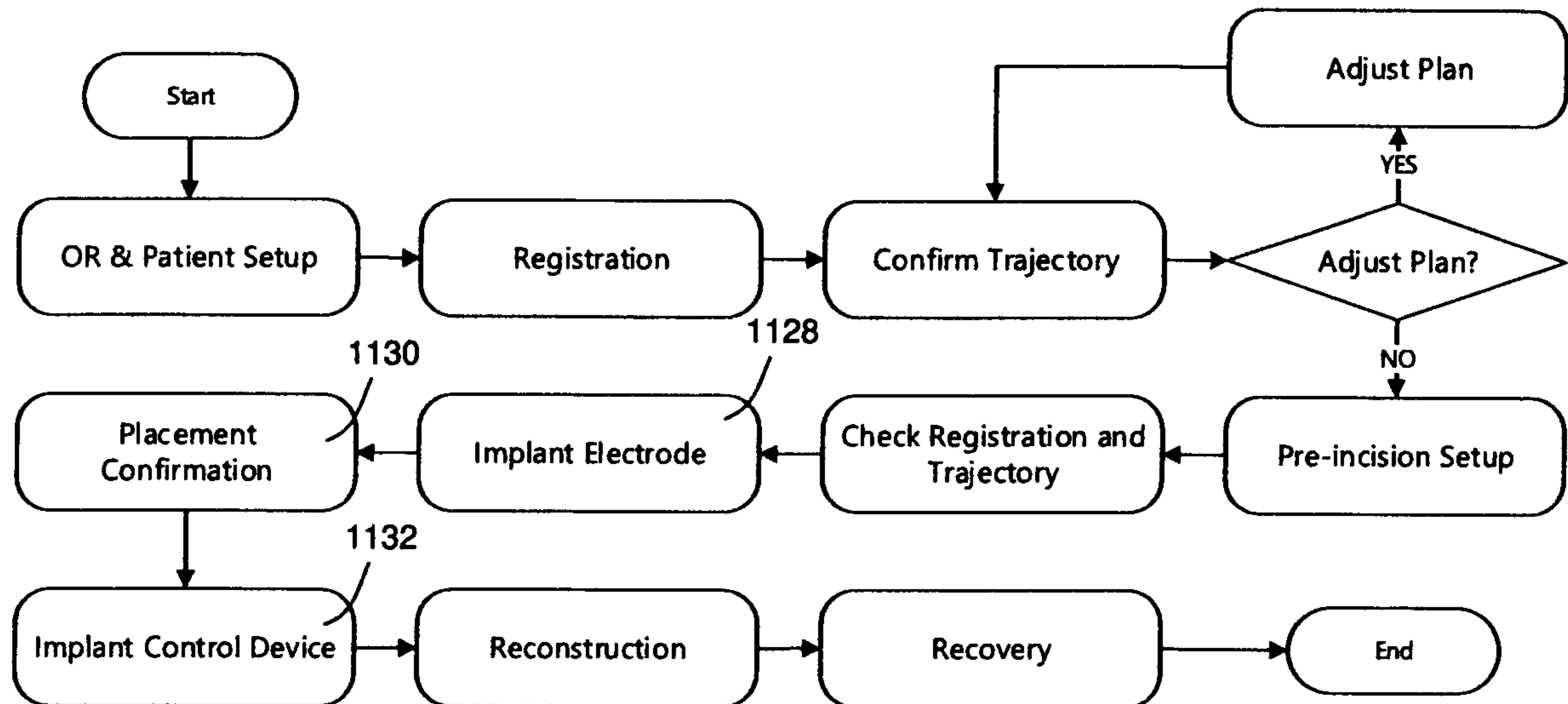
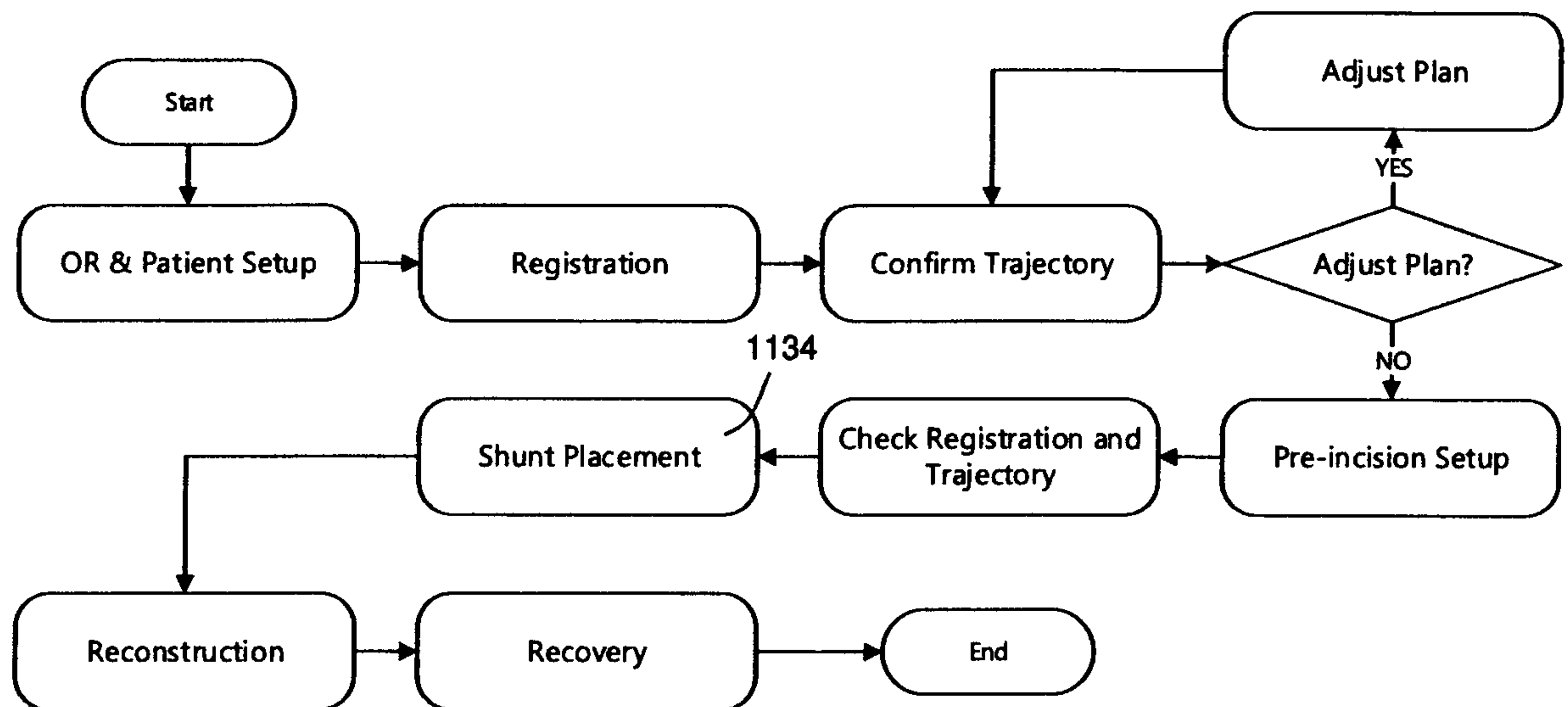


Figure 11B: Workflow steps in a frameless Brain Biopsy procedure

19/20**Figure 11C: Workflow steps in a frameless DBS procedure**

20/20**Figure 11D: Workflow steps in a catheter/shunt placement procedure**

