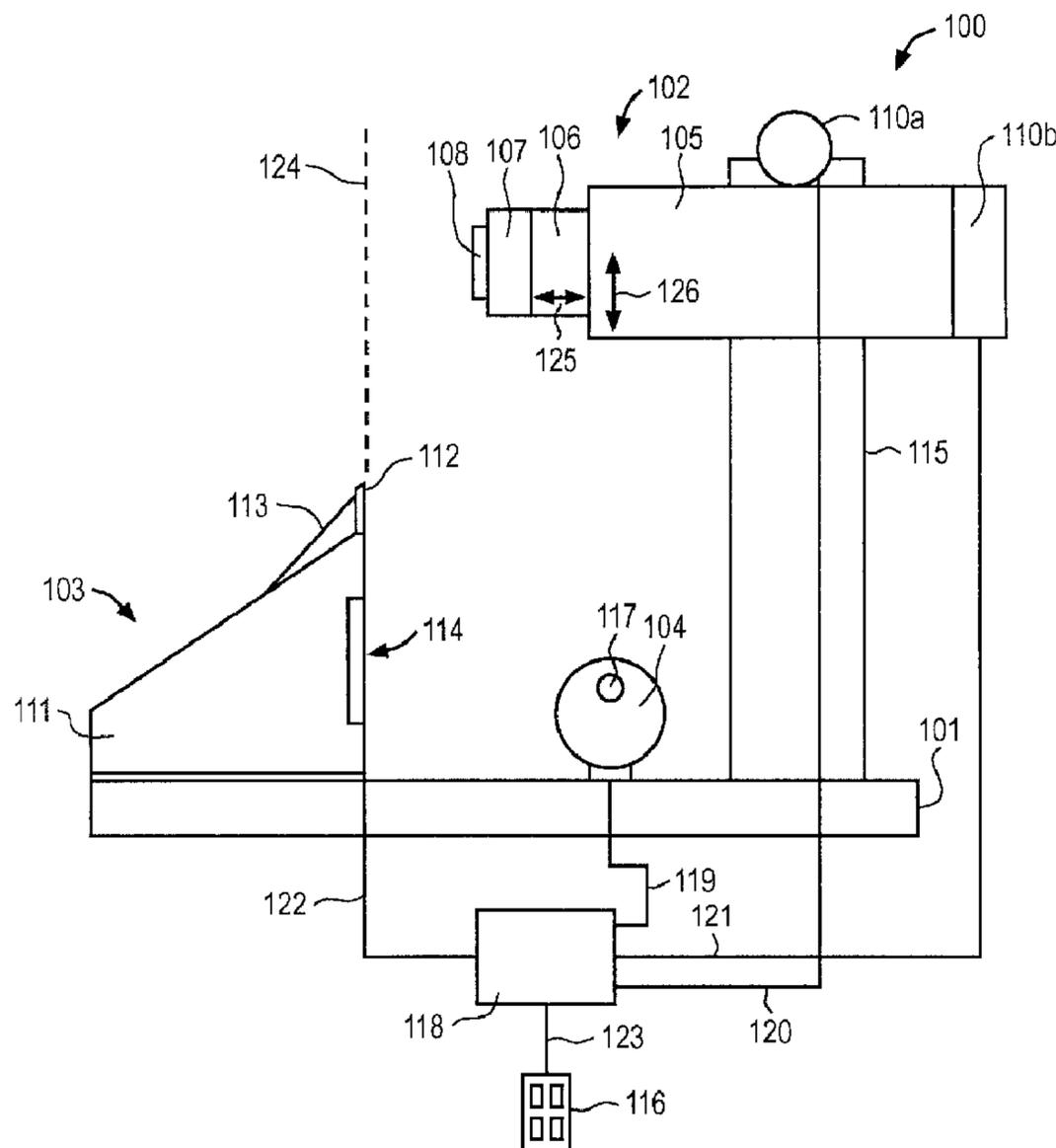




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(54) **Titre : SYSTEME D'ENTRAINEMENT DE MICROTOME A VA-ET-VIENT**  
 (54) **Title: RECIPROCATING MICROTOME DRIVE SYSTEM**



(57) **Abrégé/Abstract:**

An apparatus having a sample sectioning device including a cutting mechanism that is operable to cut sections from a sample and a sample holder that is operable to hold the sample. The apparatus further includes a drive system coupled with the sample holder

**(57) Abrégé(suite)/Abstract(continued):**

to drive movement of the sample holder and a reciprocating member coupled to the drive system to drive vertical movement of the drive system. The reciprocating member to move in a reciprocating manner within an angle of rotation of less than 180 degrees. A surface orientation sensor may further be provided that is operable to sense an orientation of a surface of the sample held by the sample holder.

### ABSTRACT

An apparatus having a sample sectioning device including a cutting mechanism that is operable to cut sections from a sample and a sample holder that is operable to hold the sample. The apparatus further includes a drive system coupled with the sample holder to drive movement of the sample holder and a reciprocating member coupled to the drive system to drive vertical movement of the drive system. The reciprocating member to move in a reciprocating manner within an angle of rotation of less than 180 degrees. A surface orientation sensor may further be provided that is operable to sense an orientation of a surface of the sample held by the sample holder.

## RECIPROCATING MICROTOME DRIVE SYSTEM

### BACKGROUND

This application is a divisional of Canadian patent application number 2,858,196 filed on December 10, 2012.

#### Field

Embodiments of the invention relate to microtomes or other tissue sample sectioning devices to produce sections of samples, specifically some embodiments relate to microtomes or other tissue sample sectioning devices that have a reciprocating drive system.

#### Background

Histology is a science or discipline associated with the processing of tissue for examination or analysis. The examination or analysis may be of the cellular morphology, chemical composition, tissue structure or composition, or other tissue characteristics.

In histology, a sample of tissue may be prepared for sectioning by a microtome or other sample sectioning device. Commonly, the tissue may be dried or dehydrated by removing most or almost all of the water from the tissue, for example by exposing the tissue to one or more dehydrating agents. After drying the tissue, clearing of the dehydrating agents may optionally be performed, and then an embedding agent (e.g., wax with added plasticizers) may be introduced or infiltrated into the dried tissue. The removal of the water and the infiltration of the embedding agent may aid in sectioning the tissue into thin sections with the microtome.

Embedding may then be performed on the tissue. During embedding, the tissue that has been dried and infiltrated with the embedding agent may be embedded in a block or other mass of wax, various polymers, or another embedding medium. Representatively, the dried and wax-infiltrated tissue may be placed in a mold and/or cassette, melted wax may be dispensed over the tissue until the mold has been filled

with the wax, and then the wax may be cooled and hardened. Embedding the tissue in the block of wax may help to provide additional support during cutting or sectioning of the tissue with a microtome.

The microtome may be used to cut thin slices or sections of the sample of tissue. Various different types of microtomes are known in the arts. Representative types include, for example, sled, rotary, vibrating, saw, and laser microtomes. The microtomes may be manual or automated. Automated microtomes may include motorized systems or drive systems to drive or automate a cutting movement between the sample from which the sections are to be cut and a cutting mechanism used to cut

the sections. It is to be appreciated that microtomes may also be used for other purposes besides just histology, and that microtomes may be used on other types of samples besides just embedded tissue.

#### BRIEF DESCRIPTION OF THE DRAWINGS

5                   The invention may best be understood by referring to the following description and accompanying drawings that are used to illustrate embodiments of the invention. In the drawings:

**FIG. 1** illustrates a schematic side view of an embodiment of a sample sectioning device.

10                   **FIG. 2A** illustrates a perspective view of a sample sectioning device in a lowered position for sample sensing.

**FIG. 2B** illustrates a perspective view of a sample sectioning device in a raised position for sample sectioning.

15                   **FIG. 3** illustrates a perspective view of a reciprocating member of a sample sectioning device.

**FIG. 4** illustrates an embodiment of a control system for controlling an operation of a sample sectioning device including a handwheel and control device.

#### DETAILED DESCRIPTION

20                   In the following description, numerous specific details, such as particular microtomes, particular cutting drive systems, particular sensors, particular sensing mechanisms, particular surface orientation measurement and/or adjustment processes, and the like, are set forth. However, it is understood that embodiments of the invention may be practiced without these specific details. In other instances, well-known mechanical components, circuits, structures and techniques have not been shown in detail in order not to  
25                   obscure the understanding of this description.

According to an aspect of the present disclosure, there is provided a method comprising: aligning a surface of a sample attached to a vertical drive member with a cutting mechanism; and performing a sample sectioning cycle to obtain a section of the sample by moving the vertical drive member in a vertical direction, wherein moving the vertical drive member comprises moving a reciprocating member attached to the vertical drive member in a reciprocating manner within an angle of rotation of less than 180 degrees.

According to an aspect of the present disclosure, there is provided a sample sectioning method comprising: sensing a surface orientation of a sample attached to a vertical drive member by producing a first vertical movement of the vertical drive member to (a) align the sample with a surface orientation sensor and then (b) move the sample away from the surface orientation sensor; aligning a surface of the sample with a cutting member, the cutting member comprising a blade operable to cut a section of the sample; and performing a sample sectioning cycle comprising: (1) moving the sample in a horizontal direction toward a cutting plane; (2) producing a second vertical movement of the vertical drive member to (a) bring the sample toward the cutting member to obtain a section of the sample; and then (b) move the vertical drive member away from the cutting member, wherein the first vertical movement of the vertical drive member comprises moving a reciprocating arm member attached to the vertical drive member in a reciprocating manner within an angle of rotation of 180 degrees and the second vertical movement of the vertical drive member comprises moving the reciprocating arm member in a reciprocating manner within an angle of 90 degrees.

**FIG. 1** illustrates a schematic side view of an embodiment of a sample sectioning device such as a microtome. In this embodiment, microtome 100 includes base member 101 having feed drive system or cutting drive system 102, mounting member 103 and handwheel 104 attached thereto. Feed drive system 102 is supported above base member 101 by support member 115. Feed drive system 102 includes vertical drive member 105, horizontal drive member 106 and sample holder 107 operable to hold sample 108. Sample 108 may include a piece of tissue that is to be

sectioned, for example, a piece of tissue embedded in a paraffin block. The cutting drive system or feed drive system 102 is operable to drive movement of sample 108 held by the sample holder 107. Motor 110a of feed drive system 102 is mechanically coupled to vertical drive member 105 and, operable to drive vertical movement of vertical drive member 105 in a direction of vertical double arrow 126. Another motor 110b of feed drive system 102 may also be mechanically coupled to horizontal drive member 106 to drive horizontal movement of horizontal drive member 106 in a direction of horizontal double arrow 125. It should be noted that terms such as "horizontal", "vertical", "top", "bottom", "upper", "lower", and the like, are used herein to facilitate the description of the illustrated device according to the orientation shown in **FIG. 1**. It is possible for other devices to replace horizontal movements with vertical movements, etc.

Referring again to the embodiment shown in **FIG. 1**, mounting member 103 includes mounting base 111 which provides a mounting surface for cutting member or mechanism 112. Cutting member or mechanism 112 may be, for example, a blade or knife of various types of materials mounted to mounting member 103, or other types of cutting mechanisms suitable for microtomes. Section receiving member 113 is positioned along one side of cutting member 112. Section receiving member 113 is dimensioned to receive a section cut from sample 108 by cutting member or blade 112. In this aspect, section receiving member 113 may have an inclined surface extending from a cutting edge of blade 112 to the surface of mounting member 103. As cutting member or blade 112 slices through sample 108, the section cut from sample 108 is separated from sample 108 and extends along section receiving member 113.

As shown, in some embodiments, microtome 100 includes a surface orientation sensor assembly 114. Surface orientation sensor assembly 114 is operable to sense or measure an orientation or angle of a surface of sample 108. The orientation or angle of the surface of sample 108 may be sensed or determined in various ways. In some embodiments, the surface of sample 108 may contact sensor assembly 114, and one or more movable portions of sensor assembly 114 may conform to an orientation of the surface of sample 108. The movement of the one or more movable portions of sensor assembly may allow microtome 100 to autonomously sense or determine the orientation of the surface of sample 108. Optical and other sensing mechanisms are also suitable.

The sensed orientation may be used to adjust or align the surface of sample 108 so that it is parallel, substantially parallel, or at least more parallel with cutting member or mechanism 112 and/or cutting plane 124 associated with cutting member or mechanism 112 than it was prior to sensing. It is advantageous that the surface of sample 108 be sufficiently aligned parallel with cutting member 112 and/or cutting plane 124 so that the sample sections cut by microtome 100 are sufficiently evenly cut. In some embodiments, microtome 100 may optionally be capable of autonomously adjusting or aligning the orientation of the surface of sample 108 parallel, sufficiently parallel, or at least more parallel, with cutting member 112 and/or cutting plane 124. Microtome 100 may have logic to autonomously sense and/or adjust an orientation of the surface of the sample relative to a cutting plane and/or cutting mechanism based on the sensed orientation. Advantageously, this may help to improve alignment accuracy and/or relieve an operator from performing the adjustment manually. Alternatively, the adjustment may be performed manually, if desired. An embodiment of a method of sectioning may include microtome 100 autonomously sensing an orientation of a surface of sample 108 using sensor assembly 114, an operator manually or microtome 100 autonomously adjusting the orientation of the surface of sample 108, and microtome 100 taking a section of sample 108 after such adjustment.

In the illustrated embodiment, sensor assembly 114 may be in a fixed positioned approximately vertically below cutting member or mechanism 112 and/or cutting plane 124. One potential advantage to positioning sensor assembly 114 vertically below cutting member 112 is that sample 108 may not need to traverse a substantial distance in the horizontal direction of arrow 125 to reach cutting member 112 and/or cutting plane 124. This may help to reduce the amount of time for sample 108 to move horizontally to cutting member 112. In one embodiment, movement in the direction of arrow 125 (horizontal movement) should be fine as a thickness of a sample section will be based in part on this translation or movement. It is appreciated that a microtome such as microtome 100 may be used to cut sample sections having a thickness in the range of 0.5 to 50 microns. Such relatively small thicknesses require translation in the direction of arrow 125 to be capable of translation within this pitch (e.g., translation of  $\pm 0.5$  micron in a direction of arrow 125). It is appreciated that significant distance to be translated in the direction of arrow 125 (e.g.  $\frac{1}{2}$  inch to 1 inch) will be time consuming. In addition, processing time can be improved by allowing vertical movement of vertical drive member 105 to be relatively faster than horizontal

movement of horizontal drive member 106. This may help to speed up the time to sense surface orientations and adjust the surface orientations.

In other embodiments, sensor assembly 114 may be movably coupled to mounting base 111 at a position between feed drive system 102 and mounting member 103, although this is not required. In this embodiment, mounting base 111 provides a support surface for sensor assembly 114 and is dimensioned and coupled to accommodate sliding of sensor assembly 114 vertically. During operation, sensor assembly 114 is operable to slide along mounting base 111 in an upward vertical direction toward feed drive system 102, and vertical drive member 105 is operable to cause feed drive system 102 to move in a downward vertical direction toward sensor assembly 114. Once sample 108 is sufficiently vertically aligned with sensor assembly 114, horizontal drive member 106 is operable to cause feed drive system 102 to move in a horizontal direction toward sensor assembly 114 in the direction of horizontal arrow 125 so that a surface of sample 108 is appropriately positioned relative to sensor assembly 114 to allow for surface orientation measurement. Once the orientation of the surface of sample 108 is determined, and realigned if appropriate, sensor assembly 114 is operable to retract in a vertical downward direction as viewed (e.g., to a retracted position away from the movement between the sample held by the sample holder and the cutting mechanism.)

Referring again to **FIG. 1**, operation of feed drive system 102 may be controlled using handwheel 104 and/or control device 116. Handwheel 104 may include handle or other pulse generating device 117 to lock the handwheel 104. Rotation of handwheel 104 may be operable to cause vertical drive member 105 to move in a vertical direction shown by vertical double arrow 126 to facilitate slicing of sample 108. In some embodiments, handwheel 104 may be a decoupled handwheel, which is not mechanically coupled to feed drive system 102. Rather, decoupled handwheel 104 may be electrically connected to an encoder (not shown) and control circuit 118 via control line 119. The rotation of decoupled handwheel 104 may cause the encoder to deliver an electrical signal to control circuit 118. Control circuit 118 is connected to motor 110a via control lines 120 and is operable to control movement of vertical drive member 105 according to the electrical signal from the encoder. Control circuit 118 is also connected to motor 110b via control line 121 to control movement of horizontal drive member 106 and is connected to sensor assembly 114 via control line 122.

In addition to signals from the encoder, signals from control device 116 may be transmitted to control circuit 118 to control or facilitate operation of sensor assembly 114, handwheel 104 and motor 110a, 110b. In some embodiments, control device 116 may be, for example, a keyboard, a capacitive sensor touch pad, or other user or data  
5 input device. In some embodiments, signals are transmitted between control device 116 and control circuit 118 via control line 123. In other embodiments, control device 116 is a wireless control device that is operable to wirelessly transmit signals to control circuit 118 and control line 123 is omitted.

**FIG. 2A** and **FIG. 2B** illustrate one embodiment of a sample sectioning device  
10 having a reciprocating member for driving a vertical movement of the feed drive system. In **FIG. 2A**, the drive member is in a lowered position suitable for sensing an orientation of the sample. In **FIG. 2B** the drive member is in a raised position suitable for sample sectioning.

Returning to **FIG. 2A**, similar to **FIG. 1**, the sample sectioning device may be a  
15 microtome 200 including sensor assembly 214 and cutting member 212 vertically aligned and attached to mounting base 211. Feed drive system 202 may be supported above base member 201 by support member 215. Feed drive system 202 may include vertical drive member 205, horizontal drive member 206 and sample holder 207 operable to hold a sample (not shown). From this view, reciprocating arm member 224  
20 for driving vertical movement of feed drive system 202 can be seen. Reciprocating arm member 224 is fixedly attached at one end to pin member 226, which extends from rotating disk member 228, and rotatably attached at the opposite end to vertical drive member 205 of feed drive system 202. Rotation of rotating disk member 228 in a reciprocating manner (i.e. alternatively forward and backward) causes pin member 226  
25 to rotate in the same direction. The reciprocal motion of pin member 226 causes the end of reciprocating arm member 224 attached to vertical drive member 205 to move in a reciprocating manner, meaning that it also moves alternately forward and backward. In some embodiments, reciprocating arm member 224 reciprocates within a 180 degree angle of rotation (e.g. moves upward 90 degrees and downward 90 degrees).  
30 Movement of reciprocating arm member 224 in this manner in turn drives vertical movement of vertical drive member 205.

**FIG. 2A** illustrates an embodiment where reciprocating arm member 224 is rotated from a first vertical position (a 0 degrees position) illustrated by **FIG. 2B** to a second vertical position (a rotation of 180 degrees with respect to the first position). At

the second vertical position, feed drive system 202, and in turn sample holder 207, is aligned with sensor assembly 214. Once at this position, horizontal drive member 206 may move laterally (horizontally viewed) to cause a sample attached to sample holder 207 to contact sensor assembly 214 so that an orientation of the sample may be determined.

Once the orientation of the sample is determined, and corrected if necessary, reciprocating arm member 224 rotates back to the first vertical position (the 0 degrees position) illustrated in **FIG. 2B** to begin a sample cutting operation. Cutting of the sample may be achieved by rotating reciprocating arm member 224, and in turn moving sample holder 207 attached to vertical drive member 205 in a vertical direction, along an approximately 90 degree angle of rotation. For example, when reciprocating arm member 224 is at the first vertical position, vertical drive member 205, and in turn the sample, is positioned above cutting member 212. Rotation of reciprocating arm member 224 approximately 90 degrees to a substantially horizontal position causes the sample to move in a downward direction across cutting member 212 resulting in removal of a section from the sample. Reciprocating arm member 224 may then be rotated 90 degrees from the substantially horizontal position back to the first vertical position to complete the cutting stroke. Reciprocating arm member 224 may continue to reciprocate within this 90 degree angle of rotation until a sufficient number of sample sections are obtained. The sample position may be adjusted in a horizontal direction by horizontal drive member 206 prior to or after each downward slicing movement to achieve the desired sample section width.

Although sample sectioning by moving reciprocating arm member 224 along a 90 degree angle of rotation is disclosed in one embodiment, it is contemplated that the angle of rotation may vary and is dictated by the size of the sample. For example, where the sample is a 30 mm by 30 mm block, a single cutting stroke or sectioning cycle requires movement of the sample approximately 35 mm in a downward vertical direction to slice a section from the sample and then movement of the sample in an upward vertical direction approximately 35 mm back to the start position. Thus, in the case of a 30 mm sample, a single cutting stroke requires vertical drive member 205 to move the sample a total distance of approximately 70 mm. Movement of reciprocating arm member 224 from the first vertical position to the horizontal position and then back to the first vertical position along the 90 degree angle of orientation translates to a 70 mm cutting stroke. Where the sample is smaller, however, a shorter cutting stroke can

be used to obtain a sample section. Representatively, where the sample is a 15 mm by 15 mm block, a single cutting stroke requires movement of the sample approximately 22 mm in a downward vertical direction to slice a section from the sample and then movement of the sample in an upward vertical direction approximately 22 mm back to the start position. In this case, a single cutting stroke requires a total vertical movement of approximately 44 mm. This shortened cutting stroke may be achieved by rotating reciprocating arm member 224 along an angle of rotation which is less than 90 degrees, for example between 0 and 60 degrees, or 0 and 45 degrees. In any case, it is recognized that since a single cutting stroke is driven by the reciprocating motion of reciprocating arm member 224, as opposed to a full 360 degree rotation, the time required to complete each cutting stroke is reduced resulting in a faster slicing operation.

In addition, the time required to complete each cutting stroke may be reduced by modifying the speed of reciprocating arm member 224 throughout the sectioning cycle. For example, in some embodiments, a relatively faster speed of movement of reciprocating arm member 224, and in turn, feed drive system 202 and/or a sample may be used during one or more non-sectioning portions of a sectioning cycle or stroke (e.g., where cutting or sectioning of a sample is not performed), whereas a relatively slower speed of movement may be used during a sectioning portion of the sectioning cycle or stroke (e.g., where cutting or sectioning of the sample is performed). Using a relatively slower speed of movement of the feed drive system and/or sample during cutting or sectioning of the sample tends to provide higher quality sections and/or more consistent sections, whereas performing one or more other non-sectioning portions of the sectioning cycle more rapidly may help to improve the overall speed of the sectioning cycle and/or may allow more sections to be produced in a given amount of time.

Representatively, microtome 200 may include logic to allow reciprocating arm member 224 to move at one speed while the sample is being cut and a second, faster speed before or after cutting of the sample. For example, the logic may allow for a sectioning length to be specified (e.g. 35 mm), reciprocating arm member 224 may move the sample at a relatively slower speed during the specified sectioning length and at a relatively faster speed just before and just after movement during the specified sectioning length (e.g. during movement of reciprocating arm member 224 from the horizontal position back to the first vertical position). The length may be selected from

among a plurality of predetermined lengths corresponding to different types of cassettes having different dimensions. In one example embodiment, microtome 200 may be operable to allow an operator to specify or indicate a sectioning length. The specification or indication of the sectioning length may be done in different ways, such as, for example, by specifying a length, selecting a length from among a plurality of predetermined lengths, specifying a type of cassette, selecting a type of cassette from among a plurality of different types of cassettes, etc. For example, when a user is ready to produce sections from a particular type of cassette, the user may make a selection of the particular type of cassette using a control device (e.g., control device 116 in **FIG. 1**), and the microtome may already be preprogrammed with a predetermined sectioning length corresponding to that particular type of cassette. During sectioning, the microtome may use a relatively slower speed of movement of the feed drive system and/or the sample over the specified sectioning length and may use relatively faster speeds of movement over one or more or substantially all other portions of the sectioning cycle. For example, immediately or just before and immediately or just after the cutting of the sample over the specified sectioning length the relatively faster speeds may be used.

In addition, microtome may include logic to initially autonomously remove a given or predetermined portion of a sample (e.g., sample 108 in **FIG. 1**). For example, the portion may include a given or predetermined thickness of paraffin, embedding material, cassette material, or other non-tissue material overlying or concealing the actual tissue material from which a section is desired to be taken (e.g., disposed between a cutting surface of the tissue material and the foremost external surface of the sample which would contact a sensing plate). By way of example, a sample may include a piece of tissue placed on a bottom of a cassette and the cassette and the tissue sample embedded in a block of embedding material. In the case of various cassettes manufactured by Sakura Finetek USA, Inc., of Torrance, California, the cassettes may include a Paraform® brand cassette material that has sectioning characteristics similar to that of paraffin and sectioning may be performed through the Paraform® brand cassette material of the cassette bottom. Once the actual tissue of the sample is exposed, a sectioning cycle to obtain slices or sections of the tissue may be commenced (e.g., the operator may press a section button or otherwise cause the microtome to take a section from the now exposed cutting surface of the tissue sample. In some embodiments, microtome 200 may include logic to allow reciprocating arm member

224 to move at a faster speed to remove these initial sections and then a relatively slower speed once sectioning of the tissue is commenced.

It is further contemplated that logic may be provided to increase the speed of movement of reciprocating arm member 224 between the second vertical position (for  
5 sensing the sample orientation) and first vertical position (for cutting the sample) so that an overall speed of the processing operation may be reduced. For example, in some embodiments, feed drive system 202 must be lowered from the raised position illustrated in **FIG. 2B** approximately 134 mm to align the sample with sensor assembly 214. In this aspect, the logic may allow for a sensing length to be specified (e.g. 134  
10 mm) and reciprocating arm member 224 may move faster along the specified sensing length in order to reduce processing time.

Movement of rotating disk member 228 may be driven by motor 210a. For example, in one embodiment, motor belt 230 is looped around an outer perimeter of rotating disk member 228. Motor 210a pulls motor belt 230 causing rotating disk  
15 member 228 to rotate in a clockwise direction (e.g. lowering vertical drive member 205) or counter-clockwise direction (e.g. raising vertical drive member 205). Motor 210a may pull motor belt 230 in alternating directions to cause reciprocating movement of reciprocating arm member 224. In addition, motor 210a may move motor belt 230 at different speeds during a sectioning operation to change the speed in which various  
20 operations (e.g. sectioning steps and non-sectioning steps) are performed throughout the sectioning cycle and/or to maintain a linear speed throughout the sectioning operation. Although a belt and rotating disk type system is disclosed, it is contemplated that any type of driving mechanism may be used to cause reciprocating arm member 224 to move in a reciprocating motion.

25 Horizontal movement of feed drive system 202 may be driven by motor 210b as previously discussed.

To facilitate alignment and vertical movement of vertical drive member 205, feed drive system 202 may be slidably attached to support member 215 by inner slide rails 220a, 220b and outer slide rails 222a, 222b. Inner slide rails 220a, 220b may have  
30 a lip that fits within grooves formed by outer slide rails 222a, 222b so that inner slide rails 220a, 220b can slide with respect to outer slide rails 222a, 222b. Outer slide rails 222a, 222b may be fixedly attached to support member 215 while inner slide rails 220a, 220b are fixedly attached to vertical drive member 205. Alternatively, outer slider rails 222a, 222b may be fixedly attached to vertical drive member 205 while inner slide rails

220a, 220b may be fixedly attached to support member 215. In either case, when vertical drive member 205 is moved by reciprocating arm member 224, outer slide rails 222a, 222b slide with respect to inner slide rails 220a, 220b so that vertical drive member 205 moves in a vertical direction.

5           **FIG. 3** illustrates a perspective view of reciprocating arm member 224 and rotating disk member 228 described in reference to **FIGS. 2A** and **2B**. From this view, it can be seen that reciprocating arm member 224 is attached to rotating disk member 228 by pin 226. Reciprocating arm member 224 may have any size and shape suitable for driving reciprocal movement of the attached drive system (not shown) between the  
10           slicing and sensing positions. For example, where a distance between the raised position of the drive member (see **FIG. 2B** cutting position) and lowered position of the drive member (**FIG. 2A** sensing position) is approximately 134 mm, reciprocating arm member 224 may have a length of approximately 67 mm such that reciprocating arm member 224 can move the drive member a total distance of approximately 134  
15           mm.

            Rotation of rotating disk member 228 along a 180 degree angle of rotation 240 rotates pin 226, which in turn drives rotation of reciprocating arm member 224 along a 180 degree angle of rotation 230. At the first vertical position 232, reciprocating arm member 224 is at a 0 degree angle of rotation. Rotation of rotating disk member 228  
20           90 degrees clockwise, causes reciprocating arm member 224 to rotate 90 degrees to the horizontal position 234. Reciprocating arm member 224 may be rotated in a reciprocating manner (i.e. forward and backward) between first vertical position 232 and horizontal position 234 during a cutting cycle or stroke.

            Rotation of rotating disk member 228 180 degrees from the 0 degree position,  
25           causes reciprocating arm member 224 to rotate 180 degrees to the second vertical position 236. At this position, the vertical drive member is aligned with the sensor assembly so that an orientation of the sample can be determined. It is contemplated that although reciprocating arm member 224 is illustrated at three positions (i.e. first vertical position 232, horizontal position 234 and second vertical position 236) other  
30           positions may be suitable for aligning the sample with the sectioning member or sensing assembly during a sensing or sensing operation, respectively. For example, sectioning of the sample may occur by moving reciprocating arm member 224 in a reciprocating manner along an angle of rotation less than 90 degrees, for example

between 0 degrees and 60 degrees, or between 0 degrees and 45 degrees, depending upon a size of the sample block.

Rotating disk member 228 may further include counterweight 238 to counterbalance feed drive system 202 attached to rotating disk member 228.

5 Counterweight 238 may, however, be optional and therefor omitted in some embodiments.

The slicing operation may proceed automatically or manually through user interaction with the system. **FIG. 4** illustrates an embodiment of a control system for controlling an operation of the microtome including a handwheel and control device.

10 Control system 460 may include handwheel 404 and control device 416. Handwheel 404 may include handle or other pulse generating device 417 to lock handwheel 404.

In some embodiments, handwheel 404 is coupled to motor 410 using a non-mechanical coupling or non-mechanical mechanism (for example an electrical coupling).

Typically, microtomes include a handwheel that is mechanically coupled to the motor.

15 Such mechanical coupling, however, adds resistance to the handwheel when the user tries to turn it. Repeated turning of such a handwheel can be taxing on the user and may at times result in medical conditions such as carpal tunnel syndrome. The non-mechanical coupling or mechanism disclosed herein may offer the advantage of reduced handwheel resistance resulting in a handwheel that is easier to turn.

20 In some embodiments, the non-mechanical coupling or mechanism includes first encoder 461. First encoder 461 may be a rotary encoder coupled to shaft 462 of handwheel 404. Rotation of handwheel 404 and in turn shaft 462 provides first encoder 461 with an angular position of handwheel 404. First encoder 461 then converts the angular position to an electrical representation (for example an analog or

25 digital code or value). This analog or digital code is transmitted to control circuit 418 via control line 419 where it is processed and used to direct movement of motor 410

and in turn feed drive 402. In some embodiments, motor 410 having feed drive 402 coupled thereto may be connected to control circuit 418 by second encoder 464. In this

aspect, shaft 463 of motor 410 may be connected to second encoder 464 so that second

30 encoder 464 may detect a position of motor 410 during the cutting operation. Encoder

464 then converts this position information to an electrical representation (for example an analog or digital code or value) and transmits the electrical representation to control

circuit 418 via control line 420. In some embodiments, control circuit 418 may control the motor based at least in part on the electrical representation of the angular position of

the handwheel. For example, since positions of both handwheel 404 and motor 410 are known, control circuit 418 can ensure that the position of handwheel 404 corresponds to, and is in alignment with, the position of motor 410 during a cutting operation. For example, rotation of handwheel 404 may not cause movement of motor 410 until a  
5 comparison of signals from the respective first and second encoders indicate that a position of handwheel 404 is aligned with a position of drive shaft of motor 410. This may tend to increase safety of operation of the microtome, especially when transferring from an automated mode of sectioning to a manual mode of sectioning. Motor 410 may be a single motor or may represent more than one motor, operable as previously  
10 discussed to drive, for example, vertical and/or horizontal movement of the microtome feed drive system.

Control device 416 may further be operable to initiate an automated cutting operation. Control device 416 may be any type of input device suitable for initiating a cutting operation. Representatively, control device 416 may include, for example, a  
15 keyboard, a keypad, a capacitive sensor touch pad, or other user data input device. In some embodiments, signals are transmitted between control device 416 and control circuit 418 via control line 423. In other embodiments, control device 416 may be a wireless control device that is operable to transmit wireless control signals to control circuit 418 and optionally receive wireless signals from control circuit 418. The  
20 control line 423 may be omitted. Wireless control device 416 may have a wireless transmitter, wireless receiver, and/or wireless transceiver, a wireless protocol stack, and other conventional components found in wireless devices. In one aspect, wireless control device 416 may be a Bluetooth capable device, although this is not required.

Control device 416 may include keys or simulated keys that can be used to  
25 control the actions of the microtome. Representatively, the keys may present graphic symbols or text corresponding to the various operations of the microtome, such as arrows corresponding to a vertical or horizontal movement of the microtome and/or other words, symbols, pictures, or the like, corresponding to, for example, slicing, stop, start, trim a bottom of a cassette, section, locking, or other microtome operations. The  
30 user selects the operation to be performed using the control device 416 and pushes the appropriate key(s) to initiate the desired operation. The control signal is transmitted from control device 416 to control circuit 418. Control circuit 418 then provides a signal to, for example, motor 410 to initiate a cutting operation. The cutting operation may then continue automatically or autonomously substantially without additional user

intervention until the user either presses a stop key or a preprogrammed cutting operation is completed. The cutting operation may also be stopped by the operator pressing on a foot switch without using his/her hands.

Sample holders capable of realigning an orientation of a surface of a sample so  
5 that they are parallel or more parallel with a cutting member and/or a cutting plane are known in the arts. In some embodiments, the feed drive system may have a multi-axis workpiece chuck or motorized chuck that is capable of adjusting an orientation of the cutting surface of the sample in two dimensions relative to a cutting member and/or cutting plane. Examples of suitable multi-axis workpiece chucks are described in U.S.  
10 Patent 7,168,694, entitled "MULTI-AXIS WORKPIECE CHUCK," by Xuan S. Bui et al., filed on January 22, 2004, and assigned to the assignee of the present application. In one embodiment, the multi-axis chuck may have a mounting assembly that retains a workpiece, such as a sample, in a substantially fixed orientation with respect to the chuck. The chuck may be motor-driven and may be rotatable about at least two axes  
15 which may be perpendicular. The chuck may be rotated manually by an operator using a controller that is in communication with one or more motors, or the microtome may autonomously rotate the chuck. One or more sensors may be used to sense a position of the chuck. According to one embodiment, each axis may have three sensors that detect a middle nominal position and end positions of the chuck. A user or the  
20 microtome may control movement of the chuck by signaling the motor to rotate the chuck to the desired position. The sensors may be used to determine whether the desired position has been reached. In one embodiment, the chuck may include first and second portions that are rotatable about at least two orthogonal axes. The first portion may rotate about a first axis and independently of the second portion. Rotation of the  
25 second portion about a second axis may cause the first portion to rotate about the second axis also. This may allow the chuck to be rotatable in multiple dimensions.

In some embodiments, a locking mechanism may also optionally be provided. After rotating the multi-axis chuck, a locking mechanism may be engaged to lock the multi-axis chuck in the desired position. This locking mechanism may be, for example,  
30 a permanent magnet solenoid, a geared motor or a rotating handle that causes the first, second, and third portions to lock by friction or other known manner. In one embodiment, a motor may be used to tighten the chuck at times when the chuck is not being adjusted. When the microtome determines to adjust the position of the sample by adjusting the chuck, or when a user decides to manually adjust the position of the tissue

sample by adjusting the chuck, the motor may be signaled to loosen the chuck to allow the chuck to be adjusted. At other times, when the position of the chuck is not being adjusted, the motor may be signaled to maintain the chuck in a tightened or locked configuration so that the position of the chuck and/or the position of a sample held by the chuck do not change unintentionally.

Returning to **FIG. 1**, in some embodiments, a sectioning cycle may include: (1) moving sample block 108 in a forward horizontal direction toward the cutting plane a predetermined distance related to the desired slice thickness; (2) moving sample block 108 in a vertical direction (for example downward) toward the cutting member to obtain a slice; (3) moving the sample block 108 in a backward or opposite horizontal direction away from the cutting plane and/or cutting member a predetermined distance; and (4) moving sample block 108 in an opposite vertical direction (for example upward) away from the cutting member. Retracting or moving the sample block 108 in a backward horizontal direction away from the cutting member helps to avoid sample block 108 contacting the cutting member during (4) when moving sample block 108 in the opposite vertical direction (for example upward) away from the cutting member. Representatively, the distance sample block 108 is retracted may correspond to a thickness of the sliced sample. Alternatively, it is contemplated that in some embodiments, the retraction step may be omitted. The slicing cycle may be repeated until a desired number of slices are obtained.

In the foregoing specification, the invention has been described with reference to specific embodiments thereof. It will, however, be evident that various modifications and changes can be made thereto. The specification and drawings are, accordingly, to be regarded in an illustrative rather than a restrictive sense.

In the description above, for the purposes of explanation, numerous specific details have been set forth in order to provide a thorough understanding of the embodiments of the invention. It will be apparent however, to one skilled in the art, that one or more other embodiments may be practiced without some of these specific details. The particular embodiments described are not provided to limit the invention but to illustrate it. In other instances, well-known

circuits, structures, devices, and operations have been shown in block diagram form or without detail in order to avoid obscuring the understanding of the description.

It will also be appreciated, by one skilled in the art, that modifications may be made to the embodiments disclosed herein, such as, for example, to the sizes, shapes, configurations, couplings, forms, functions, materials, and manner of operation, and assembly and use, of the components of the embodiments. All equivalent relationships to those illustrated in the drawings and described in the specification are encompassed within embodiments of the invention. Further, where considered appropriate, reference numerals or terminal portions of reference numerals have been repeated among the figures to indicate corresponding or analogous elements, which may optionally have similar characteristics.

Various operations and methods have been described. Some of the methods have been described in a basic form, but operations may optionally be added to and/or removed from the methods. In addition, while a particular order of the operations according to example embodiments has been described, it is to be understood that that particular order is exemplary. Alternate embodiments may optionally perform the operations in different order, combine certain operations, overlap certain operations, etc. Many modifications and adaptations may be made to the methods and are contemplated.

One or more embodiments include an article of manufacture (e.g., a computer program product) that includes a machine-accessible and/or machine-readable medium. The medium may include, a mechanism that provides (e.g., stores) information in a form that is accessible and/or readable by the machine. The machine-accessible and/or machine-readable medium may provide, or have stored thereon, a sequence of instructions and/or data structures that if executed by a machine causes or results in the machine performing, and/or causes the machine to perform, one or more or a portion of the operations or methods disclosed herein. In one embodiment, the machine-readable medium may include a tangible non-transitory machine-readable storage media. For example, the tangible non-transitory machine-readable storage media may include a floppy diskette, an optical storage medium, an optical disk, a CD-ROM, a magnetic disk, a magneto-optical disk, a read only memory (ROM), a programmable ROM (PROM), an erasable-and-programmable ROM (EPROM), an electrically-erasable-and-programmable ROM (EEPROM), a random access memory (RAM), a static-RAM (SRAM), a dynamic-RAM (DRAM), a Flash memory, a phase-change memory, or a

combinations thereof. The tangible medium may include one or more solid or tangible physical materials, such as, for example, a semiconductor material, a phase change material, a magnetic material, etc.

5 It should also be appreciated that reference throughout this specification to "one embodiment", "an embodiment", or "one or more embodiments", for example, means that a particular feature may be included in the practice of the invention. Similarly, it should be appreciated that in the description various features are sometimes grouped together in a single embodiment, Figure, or description thereof for the purpose of streamlining the disclosure and aiding in the understanding of various inventive  
10 aspects. This method of disclosure, however, is not to be interpreted as reflecting an intention that the invention requires more features than are expressly recited. Rather, inventive aspects may lie in less than all features of a single disclosed embodiment.

CLAIMS:

1. A sample sectioning method comprising:

sensing a surface orientation of a sample attached to a vertical drive member by producing a first vertical movement of the vertical drive member to (a) align the sample  
5 with a surface orientation sensor and then (b) move the sample away from the surface orientation sensor;

aligning a surface of the sample with a cutting member, the cutting member comprising a blade operable to cut a section of the sample; and

performing a sample sectioning cycle comprising: (1) moving the sample in a  
10 horizontal direction toward a cutting plane; (2) producing a second vertical movement of the vertical drive member to (a) bring the sample toward the cutting member to obtain a section of the sample; and then (b) move the vertical drive member away from the cutting member, wherein the first vertical movement of the vertical drive member comprises moving a reciprocating arm member attached to the vertical drive member in a reciprocating manner  
15 within an angle of rotation of 180 degrees and the second vertical movement of the vertical drive member comprises moving the reciprocating arm member in a reciprocating manner within an angle of 90 degrees.

2. The sample sectioning method of claim 1, wherein the angle of rotation is less than 90 degrees.

20 3. The sample sectioning method of claim 1, further comprising specifying a configurable sectioning length, and wherein performing the sample sectioning cycle comprises moving the reciprocating arm member at a relatively slower speed of movement when cutting the section from the sample over the specified sectioning length and moving the reciprocating arm member at a relatively faster speed of movement at least one of  
25 immediately before or immediately after the movement over the specified sectioning length.

4. The sample sectioning method of any one of claims 1-3, wherein the method comprises using a sample sectioning device, the sample sectioning device comprising:

the cutting member that is operable to cut sections from the sample;

5 a drive system comprising the vertical drive member, a horizontal drive member and a sample holder operable to hold the sample; and

the reciprocating arm member coupled to the drive system to drive vertical movement of the drive system.

10 5. The sample sectioning method of any one of claims 1-3, wherein prior to moving the vertical drive member away from the cutting member as part of the second vertical movement of the vertical drive member, the method comprises moving the sample in a horizontal direction away from the cutting plane.



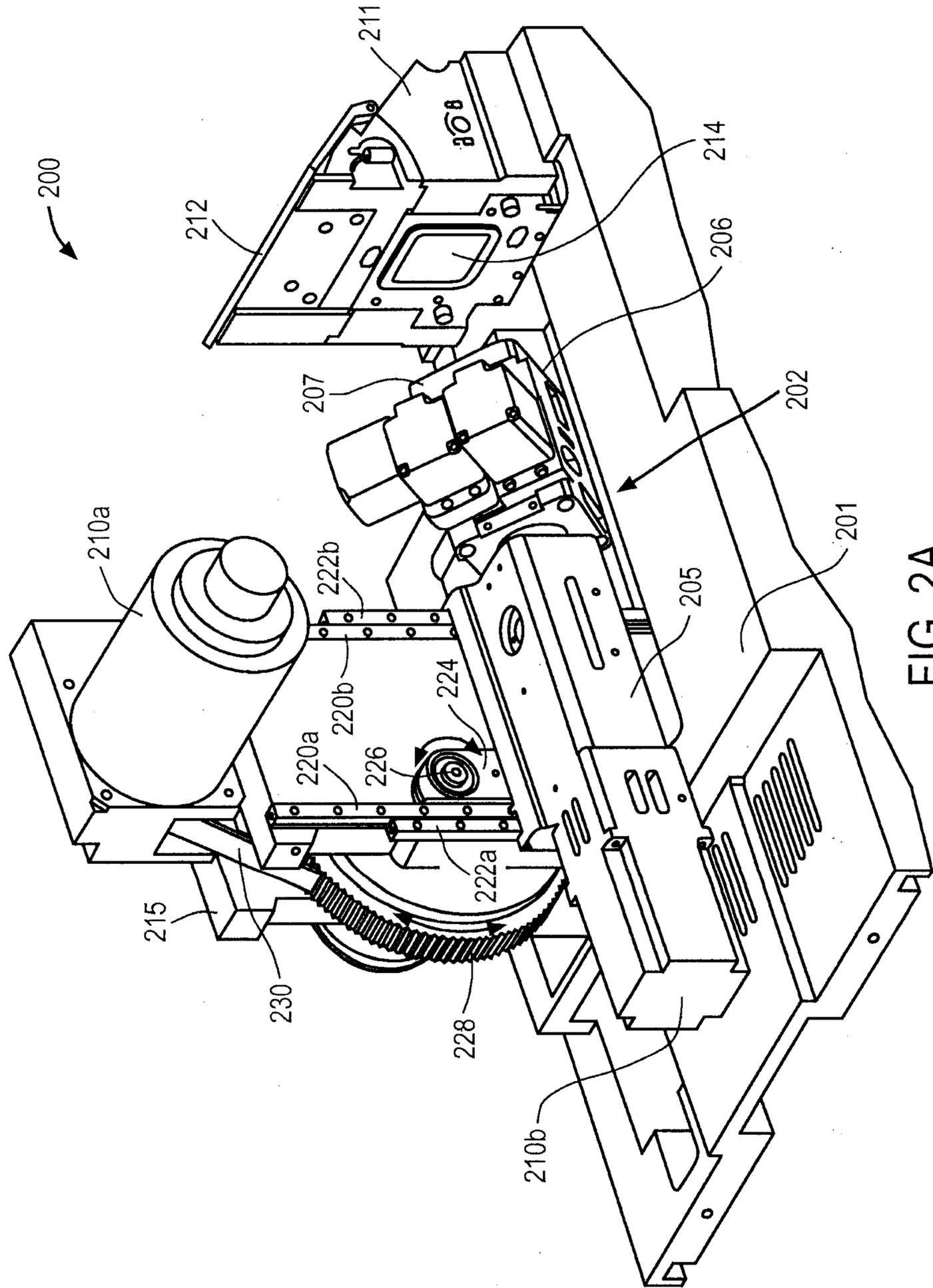


FIG. 2A

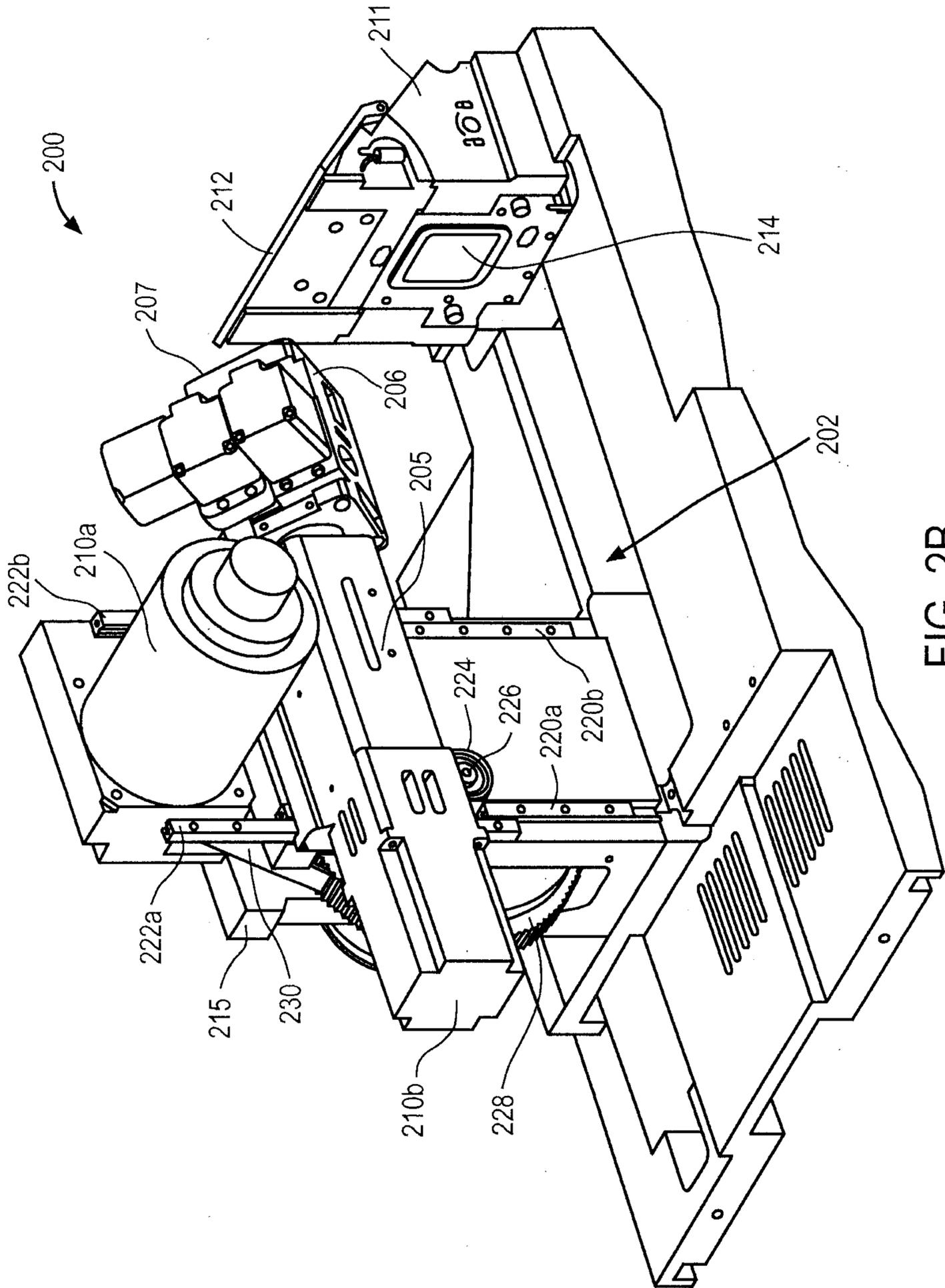


FIG. 2B

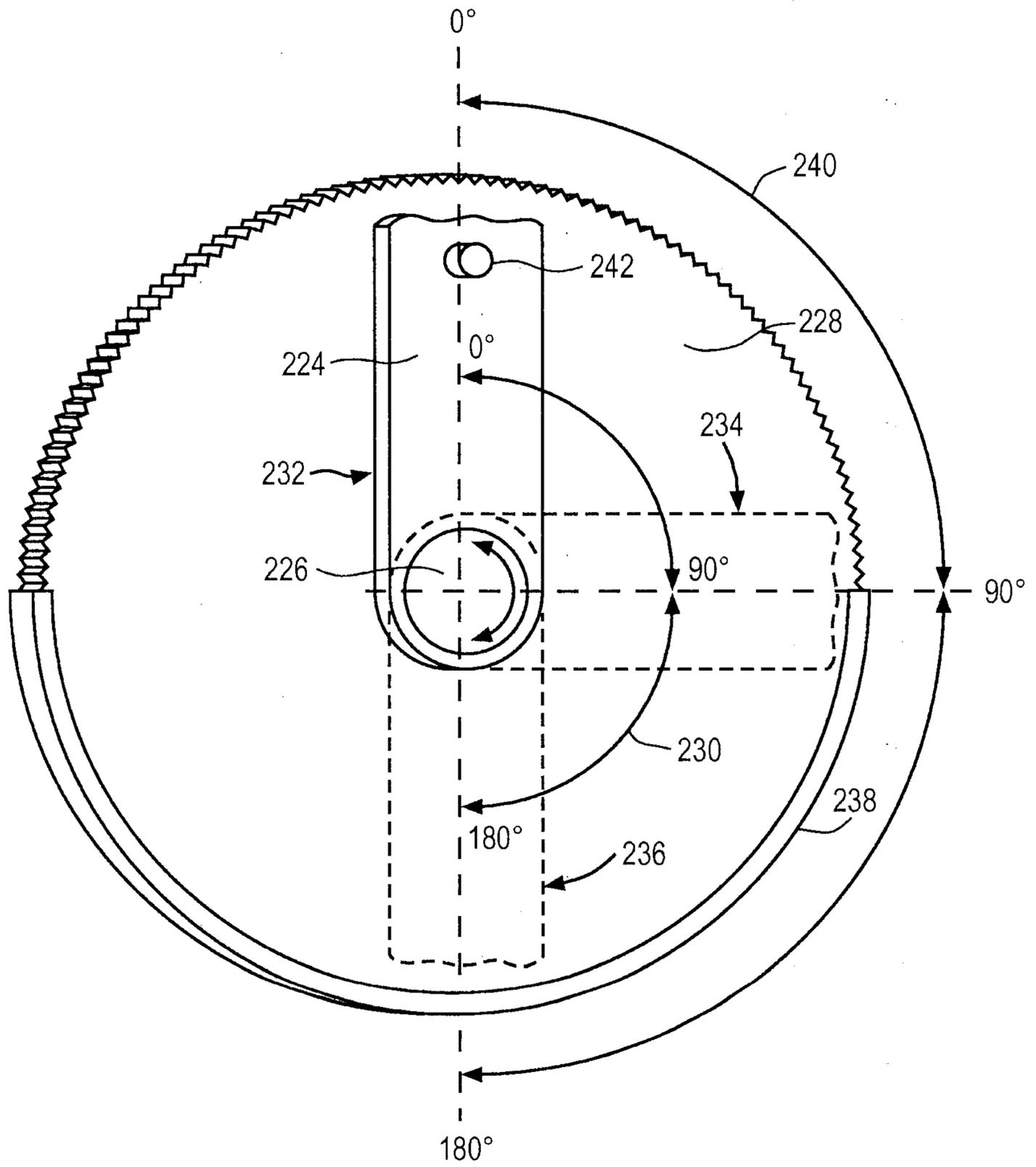


FIG. 3

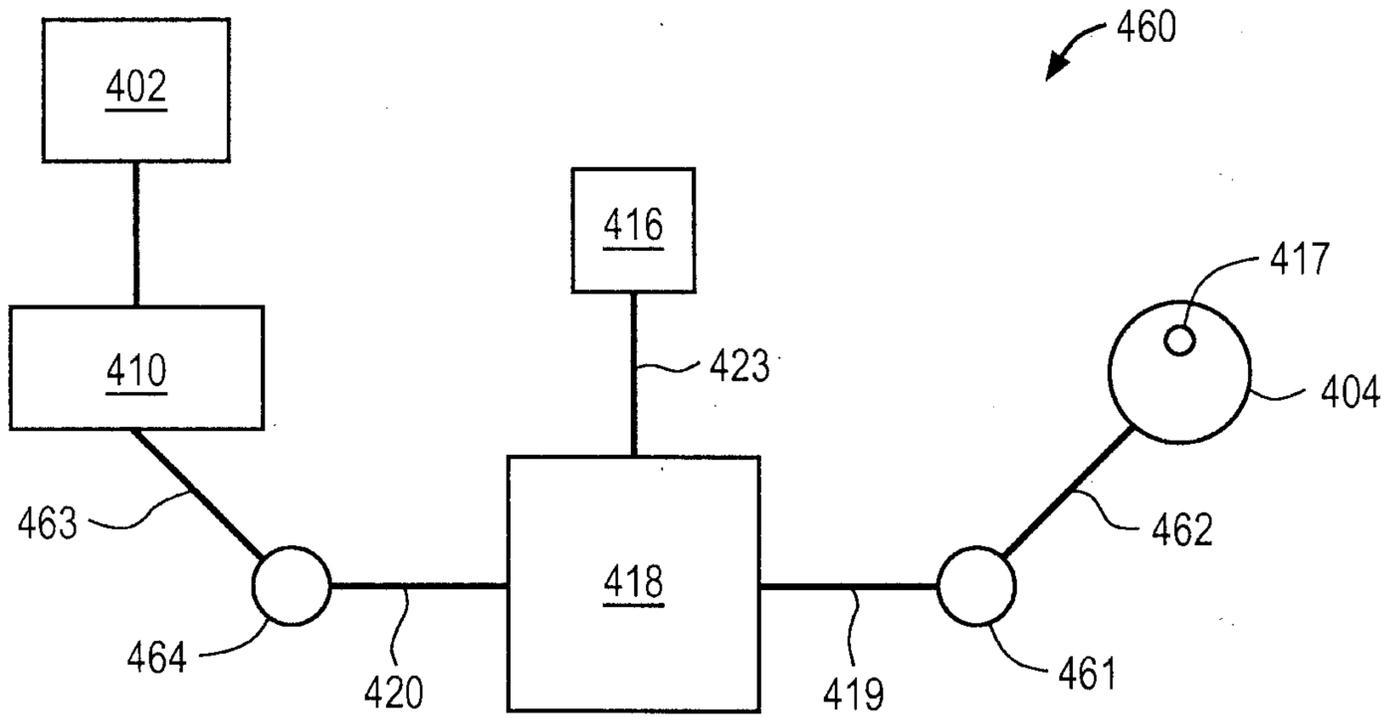


FIG. 4

