Table of Contents

Introduction xi

Chapter 1. Characteristics and State of the Art 1
Etienne DOMBRE, Michel DE MATHELIN and Jocelyne TROCCAZ

1.1 Introduction 1
1.1.1. Characteristics of medical robotics 1
1.1.2. Potential advantages of using a robot in a medical procedure 5
1.2. State of the art 7
1.2.1. Surgery of the head and neck 8
1.2.2. Orthopedic surgery 13
1.2.3. Mini-invasive or laparoscopic surgery 17
1.2.4. Interventional radiology and percutaneous procedures 23
1.2.5. Remote ultrasound 29
1.2.6. Radiotherapy and radiology 33
1.2.7. Other applications 39
1.3. Conclusion 42
1.4. Bibliography 42

Chapter 2. Medical Robotics in the Service of the Patient 55
Alexandre MOREAU-GAUDRY, Philippe CINQUIN

2.1. Introduction 55
2.1.1. Medical robotics: a field in full development 55
2.1.2. How and why has there been such development? 56
2.1.3. Medical service: a complex notion 57
2.2. A cycle of medical service growth 58
2.2.1. The actors 58
2.2.2. A model for the development of the medical service 61
2.2.3. Development diagram 63

2.3. A case study: the ViKY robotic endoscope support system 64
2.3.1. The context 64
2.3.2. ViKY and the progression of medical service 64
2.3.3. Relevance of the evaluation of the medical service 66
2.4. Conclusion 67
2.5. Bibliography 67

Chapter 3. Inter-operative Sensors and Registration 69
Jocelyne TROCCAZ

3.1. Introduction. 69
3.1.1. Summary of the context and the problem. 69
3.1.2. Notions of registration, calibration and tracking. 70
3.2. Intra-operative sensors 72
3.2.1. Imaging sensors. 72
3.2.2. Position sensors. 74
3.2.3. Surface sensors 75
3.2.4. Other sensors 76
3.3. Principles of registration 76
3.3.1. Notations and definitions 76
3.3.2. Nature of the transformation 77
3.3.3. Matched information. 78
3.3.4. Similarity metrics. 79
3.3.5. 3D/3D rigid registration 84
3.3.6. Open questions 86
3.4. Case studies. 87
3.4.1. Case no. 1 (interventional radiology) 87
3.4.2. Case no. 2 88
3.4.3. Case no. 3 (Velocityy) 90
3.4.4. Case no. 4 92
3.5. Discussion and conclusion 96
3.6. Bibliography 97

Chapter 4. Augmented Reality 101
Stéphane NICOLAU, Luc SOLER, Jacques MARESCAUX

4.1. Introduction. 101
4.2. 3D modeling of abdominal structures and pathological structures . . . 104
4.3. 3D visualization system for planning. 107
4.4. Interactive AR 108
4.4.1. Concept. 108
4.4.2. An example application 108
4.4.3. The limits of such a system 110
4.5. Automatic AR 110

4.5.1. Augmented reality with fixed camera(s) . . . 111
4.5.2. AR with a mobile camera . . . 120
4.6. Taking distortions into account . . . 122
4.7. Case Study . . . 124
4.7.1. Percutaneous punctures . . . 124
4.7.2. Bronchoscopic Navigation . . . 126
4.7.3. Neurosurgery . . . 127
4.8. Conclusions . . . 129
4.9. Bibliography . . . 130

Chapter 5. Design of Medical Robots . . . 141
Etienne DOMBRE, Philippe POIGNET and François PIERROT

5.1. Introduction . . . 141
5.2. From the characterization of gestures to the design of robots . . . 145
5.2.1. Analysis of the gesture . . . 145
5.2.2. Kinematic and dynamic specifications . . . 145
5.2.3. Kinematic choices . . . 149
5.3. Design methodologies . . . 157
5.3.1. Concept selection . . . 158
5.3.2. Optimization of design parameters . . . 161
5.4. Technological choices . . . 165
5.4.1. Actuators . . . 165
5.4.2. Sensors . . . 166
5.4.3. Material . . . 167
5.5. Security . . . 167
5.5.1. Introduction . . . 167
5.5.2. Security and dependability . . . 168
5.5.3. Risks reduction in medical robotics . . . 168
5.6. Conclusion . . . 171
5.7. Bibliography . . . 172

Chapter 6. Vision-based Control . . . 177
Jacques GANGLOFF, Florent NAGEOTTE and Philippe POIGNET

6.1. Introduction . . . 177
6.1.1. Configurations of the imaging device . . . 178
6.1.2. Type of measurement . . . 179
6.1.3. Type of control . . . 181
6.2. Sensors . . . 183
6.2.1. Imaging devices . . . 184
6.2.2. Localizers . . . 193
6.3. Acquisition of the measurement . . . 193
6.3.1. Acquisition of geometric primitives . . . 194

6.3.2. Tracking of anatomical targets 202
6.3.3. Review of methods for image processing 214
6.4. Control 216
6.4.1. Modeling the visual servoing loop 216
6.4.2. Online identification of the interaction matrix 221
6.4.3. Control laws 223
6.5. Perspectives 224
6.6. Bibliography 225

Chapter 7. Interaction Modeling and Force Control 233
Philippe POIGNET and Bernard BAYLE

7.1. Modeling interactions during medico-surgical procedures 233
7.1.1. Introduction 233
7.1.2. Properties of tissues with small displacements 234
7.1.3. Non-viscoelastic models 237
7.1.4. Estimation of force models 238
7.1.5. Case study: needle-tissue interactions during a percutaneous intervention 239
7.2. Force control 243
7.3. Force control strategies 244
7.3.1. Implicit force control 244
7.3.2. Explicit force control 247
7.3.3. Stability 250
7.3.4. Choice of a control architecture 251
7.3.5. Application examples 251
7.4. Conclusion 263
7.5. Bibliography 263

Chapter 8. Tele-manipulation 269
Bernard BAYLE and Laurent BARBÉ

8.1. Introduction 269
8.1.1. The limitations of autonomy 269
8.1.2. Non-autonomous modes of intervention 270
8.1.3. Tele-manipulation in the medical field: interest and applications 270
8.2. Tele-manipulation and medical practices 271
8.2.1. Background 271
8.2.2. Action and perception modalities 273
8.2.3. Technology 275
8.3. Tele-manipulation with force feedback 278
8.3.1. Introduction 278
8.3.2. Modeling master-slave tele-manipulators (MST) 279

8.3.3. Transparency and stability 281
8.3.4. Bilateral tele-operation control schemes 284
8.3.5. Improvement of existing techniques for medical issues 292
8.3.6. Example: tele-operated needle insertion in interventional radiology 294
8.3.7. Prospects 298
8.4. Bibliography 298

Chapter 9. Comanipulation 303
Guillaume MOREL, Jérôme SZEWCZYK and Marie-Aude VITRANI

9.1. Introduction 303
9.1.1. Tele-manipulate, but without the distance 303
9.1.2. Definitions 305
9.1.3. Features and applications in medical and surgical robotics 307
9.1.4. A word about terminology 308
9.1.5. Contents 308
9.2. General principles of comanipulation 309
9.2.1. Serial comanipulation 309
9.2.2. Parallel comanipulation 313
9.3. Serial comanipulation: intelligent active instrumentation 316
9.3.1. Dexterous instruments for minimally-invasive surgery 316
9.3.2. Tremor filtering in microsurgery 322
9.3.3. Compensation of physiological movements 326
9.4. Parallel comanipulation 331
9.4.1. Comanipulation in transparent mode 331
9.4.2. Passive, active, static and dynamic guides 334
9.4.3. Increase the quality of the tactile perception 340
9.5. A human in the loop 343
9.6. Bibliography 346

Chapter 10. Towards Intracorporeal Robotics 351
Etienne DOMBRE, Nicolas CHAILLET and Michel DE MATHELIN

10.1. Introduction 351
10.2. Mini-manipulators/tele-operated instrument holders 352
10.2.1. Objectives 352
10.2.2. General description 353
10.2.3. Challenges 356
10.3. Robotized colonoscopes and autonomous capsules 357
10.3.1. Objectives 357
10.3.2. General description 358
10.3.3. Challenges 360
10.4. Active catheters 362

10.4.1. Objectives 362
10.4.2. General description 363
10.4.3. Challenges 363
10.5. Evolution of surgical robotics 366
10.5.1. Towards more autonomous robots 366
10.5.2. Towards a much less invasive surgery 369
10.5.3. Towards the bio-nanorobotics 371
10.6. Additional information 386
10.6.1. Preamble 386
10.6.2. The shape memory alloys (SMA) 387
10.6.3. Electroactive polymers 387
10.7. Bibliography 388

Conclusion 397

Notations 399

Medical Glossary 401

List of Authors 407

Index 409