

Telemanipulation and Telestration for Microsurgery

Computer Integrated Surgery II Spring, 2012

Orhan Ozguner & Robert Eisinger, under the supervision of Prof. Russell Taylor and Marcin Balicki

Introduction

- Retinal surgery and other microsurgeries requires fine control and great concentration.
- Surgeons become exhausted and are often working close to the limits of human dexterity.
- Cooperative control systems effectively aid in these problems (i.e. hand tremor reduction via the Steady Hand Eye Robot).
- A telemanipulation system has implications for cooperative surgery, education, and communication.

Algorithm

Telemanipulation

 Master/slave system for controlling the Steady Hand Eye Robot by using the Phantom Omni Haptic Device

Telestration

- Use the Omni to graphically annotate the 3D display during surgery
- The Omni has many advantages (haptic feedback, 3D control, cheap, etc.)



Technical Approach

- 1) Identify error in the already-existing framework
- 2) Fix the error (via Cartesian Motion Control)
- 3) Extend the telemanipulation platform with bilateral cooperation
- 4) Set up workstation to simulate real telemanipulation environment



- Inspired by sport telestrators
- Useful for communication and educating surgeon trainees and eventually...defining virtual fixtures.
- The primary surgeon may continue with the surgery as the secondary surgeon uses the Omni for telestration



Technical Approach

- Simple scaling algorithm and graphics software
- Widget-based sidebar approach



- Highly modular
- Each widget is responsible for a single graphics object
 - Straight line
 - Free hand drawing
 - Square
 - Circle

Networking and System Setup

- Individual components connected to a Global Component Manager
- The Teleopcomponent Application mediates actions related to telemanipulation and telestration



Future Work

- Integrate tool tracker with particle filtering to then have the capability of drawing virtual fixtures via telestration
- Additional telestration widgets
- Bimanual telemanipulation

Lessons Learned

- Familiarity with Constrained Optimization Algorithm
- Familiarity with CISST development framework

Acknowledgements

- Mentors, especially Marcin Balicki, for enormous help and support
- Professor Russell Taylor for valuable feedback

