

Search history

Search 1: PASSIVE and ORTHOSES and REHABILITATION (Results 5)

Title: A **REHABILITATION** ROBOT FOR LOWER LIMB GAIT THERAPY

Abstract: Source: IN04757MU2015A [EN] The present invention provides a **rehabilitation** robot (100) comprising: an active planar parallel manipulator (200) having plurality guiding rails (210a, 210b, 210c, 210d 230, 240) and at least three rotary joints, adjusted to provide a workspace for **rehabilitation** said lower limb. The end effector of the parallel manipulator coupled to a foot plate of at least one **passive** adjustable leg **orthoses** (700), comprises an arrangement of plurality of gears (500, 600) actuated to provide an angular movement to said foot plate. The **passive** adjustable leg **orthoses** (700) operable due to said angular movement of said foot plate, wherein said **passive** adjustable leg **orthoses** (700) comprises at least three serial links and at least two rotary joint for holding and supporting said lower limb, and measure said angular movement of said lower limb.

Classifications:

International (IPC 8-9): A61F5/00 (Advanced/Invention)

Family:

Publication number	Publication date	Application number	Application date
IN04757MU2015 A	20170623	IN2015MU04757	20151218

Priority:

IN2015MU04757 20151218

Probable Assignee: INDIAN INST OF TECHNOLOGY INDORE

Assignee(s): INDIAN INST OF TECHNOLOGY INDORE

Inventor(s): MOHAN SANTHAKUMAR ; MOHANTA JAYANT KUMAR

Title: ARTIFICIAL HUMAN LIMBS AND JOINTS EMPLOYING ACTUATORS, SPRINGS, AND VARIABLE-DAMPER ELEMENTS

Abstract: Source: US2006249315A [EN] Biomimetic Hybrid Actuators employed in biologically-inspired musculoskeletal architectures employ an electric motor for supplying positive energy to and storing negative energy from an artificial joint or limb, as well as elastic elements such as springs, and controllable variable damper components, for **passively** storing and releasing energy and providing adaptive stiffness to accommodate level ground walking as well as movement on stairs and surfaces having different slopes.

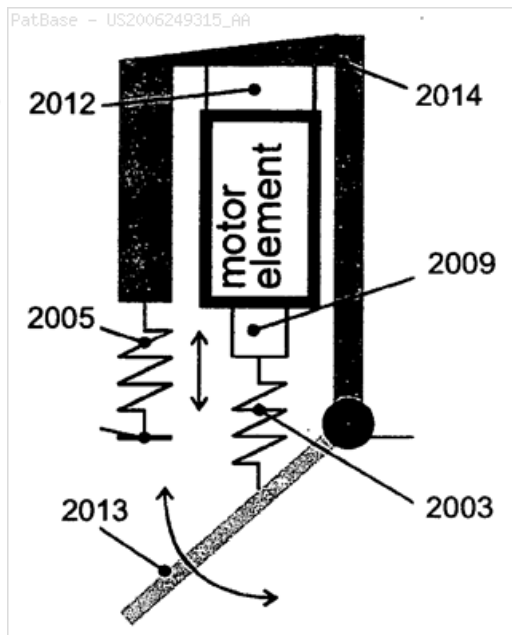
Classifications:

International (IPC 8-9): A61B5/103 A61F2/30 A61F2/32 A61F2/48 A61F2/60 A61F2/62 A61F2/64 A61F2/66 A61F2/68 A61F2/70 A61F2/72 A61F2/74 A61F2/76 A61F5/00 A61F5/01 A61F5/052 A61G5/00 A61H A61H1/00 A61H3/00 B25J19/00 B25J19/02 B25J5/00 B25J9/00 B25J9/10 B25J9/16 B25J9/18 B62D51/06 B62D57/032 C03C21/00 F16H25/00 F16H25/20 F16H25/22 F16H55/14 G01L5/00 G01P21/00 G05B19/04 G05B21/00 G06F19/00 H02K41/02 H02K7/06 H04M1/02 H04M1/18 (Advanced/Invention); A61F2/50 A61F2/60 A61F2/64 A61F2/66 A61F2/68 A61F2/70 A61F2/72 A61F2/74 A61F2/76 A61F5/01 A61H3/00 B25J9/00 B25J9/18 F16H25/00 F16H25/20 G01P21/00 H02K41/02 H02K7/06 H02K7/116 (Advanced/Non-invention); A61B5/103 A61F2/48 A61F2/50 A61F2/60 A61H3/00 B25J9/18 B62D51/00 F16H25/00 G05B19/04 H02K41/02 (Core/Invention); A61F2/62 A61F2/68 A61G5/00 F16H25/00 H02K41/02 (Core/Non-invention)

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US: 1/1 180/8.1 180/8.100P 318/568.1 318/568.12 318/568.16 318/568.17 318/568.2 600/587 600/587P 601/34 601/34P 601/34S 601/5 602/16 602/16S 602/23 602/23S 602/26 602/27 623/18.11 623/18.110S 623/22.11 623/22.110P 623/24 623/24P 623/25 623/25 623/27 623/27P 623/32 623/32P 623/39 623/39P 623/39S 623/43 623/44 623/46 623/46S 623/47 623/47S 623/49 623/49S 623/50 623/50P 623/50S 623/51 623/51P 623/51S 623/52 623/52S 623/53 623/53S 65/30.1 65/30.100S 65/30.14 65/30.140P 65/355 65/355S 700/245 700/246 700/250 700/250P 700/251 700/253 700/258 700/260 700/261 73/1.38 901/1 901/46 901/9



Family:

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Priority:

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Inventor(s): POPOVIC MARKO ; PALUSKA DANIEL ; MAGNUSSON LEE ; HOFMANN ANDREAS ; HERR HUGH

Agent(s): SPRUSON AND FERGUSON; SIM AND MCBURNEY; SMART AND BIGGAR; MARKS AND CLERK; HOWARD PAUL NICHOLAS; CARPMAELS AND RANSFORD LLP; SOMERVELL THOMAS RICHARD; LAWRENCE JOHN; GILLARD MATTHEW PAUL; MEARS ANDREW DAVID; FURUYA SATOSHI; MIZOBE TAKAHIKO; CHARLES G CALL; PROSKAUER ROSE LLP; NORMA E HENDERSON,HENDERSON PATENT LAW; NORMA E HENDERSON HENDERSON PATENT LAW; CHARLES G; WOLF GREENFIELD AND SACKS P C; WOLF GREENFIELD AND SACKS PC; HAMILTON BROOK SMITH AND REYNOLDS PC; KACVINSKY DAISAK BLUNI PLLC BOSTON; KACVINSKY DAISAK BLUNI PLLC; SAARMAA ERIK; HENDERSON NORMA E; MAYER ROBERT S; THOMAS C DOUGLASS

Designated states: AE AG AL AM AO AT AU AZ BA BB BE BF BG BH BJ BR BW BY BZ CA CF CG CH CI CL CM CN CO CR CU CY CZ DE DK DM DO DZ EC EE EG ES FI FR GA GB GD GE GH GM GN GQ GR GT GW HN HR HU ID IE IL IN IS IT JP KE KG KM KN KP KR KZ LA LC LI LK LR LS LT LU LV LY MA MC MD ME MG MK ML MN MR MT MW MX MY MZ NA NE NG NI NL NO NZ OM PE PG PH PL PT QA RO RS RU SC SD SE SG SI SK SL SM SN ST SV SY SZ TD TG TH TJ TM TN TR TT TZ UA UG US UZ VC VN ZA ZM ZW

Title: **ORTHOSES** FOR JOINT **REHABILITATION**

Abstract: Source: US2005101887A [EN] **Orthoses** with microprocessor control placed around the joint of a patient are used to perform and to monitor isometric, range-of-motion, proprioception and isotonic exercises of the joint. A variety of improved hardware elements result in an orthosis that is easier to use and interacts more efficiently with the controller to allow the monitoring of a greater range of motions while holding down cost and provide suitable accurate evaluation of the exercises. Efficient ways of programming the exercises, monitoring the exercises and evaluating the exercise provide a comprehensive program for the **rehabilitation** of an injured or weakened joint.

Classifications:

International (IPC 8-9): A61B5/103 A61B5/117 A61F5/01 A61H1/02 A61H3/00 A63B15/02 A63B21/00 A63B23/035 A63B23/04

A63B24/00 A63B71/00 G01L5/00 G06F19/00

G06F19/10 (Advanced/Invention);

A61F5/01 A63B23/035 (Core/Invention)

International (IPC 1-7): A61F5/00 A61H1/02 A63B21/00 A63B23/035 G01L5/00

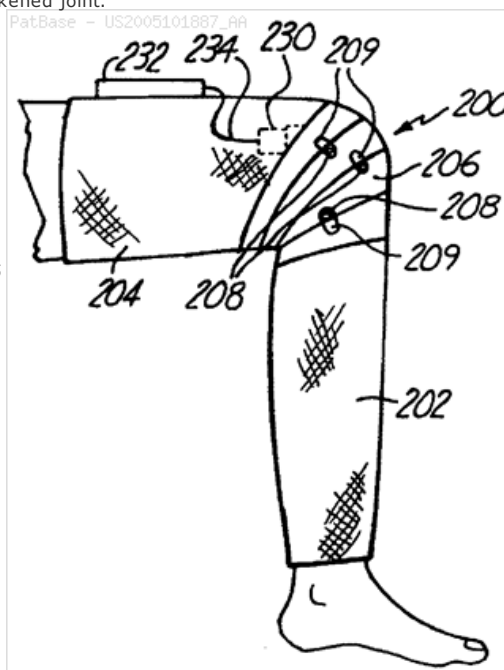
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G06F19/34N K63B220/51

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Family:

Publication number	Publication date	Application number	Application date
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Priority:

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Inventor(s): TRACEY TIMOTHY ; DUANE P M OYEN ; BOYD JOEL ; STARK JOHN ; OYEN DUANE ; LOHMANN ARTHUR ; OYEN DUANE PM

Agent(s): MARKS AND CLERK; MASUI CHUJI; SHAMOTO ICHIO; KOBAYASHI YASUSHI; TOMITA HIROYUKI; TAKEUCHI SHIGEO; PATTERSON THUENTE SKAAR AND CHRISTENSEN PA 4800 IDS CENTER; PATTERSON THUENTE SKAAR AND CHRISTENSEN PA; DARDI AND ASSOCIATES PLLC, US BANK PLAZA; DARDI AND ASSOCIATES PLLC US BANK PLAZA; PETER S; SCHWEGMAN LUNDBERG AND WOESSNER PA

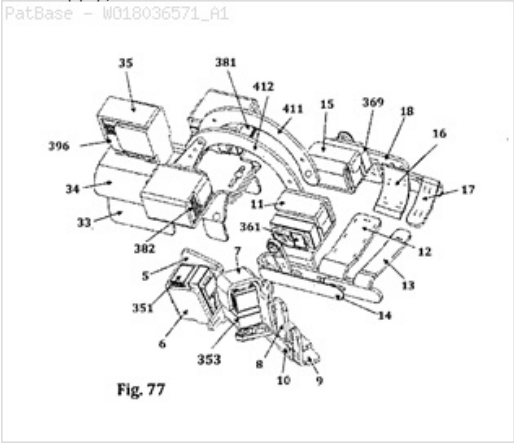
Designated states: AM AT AZ BE BY CA CH CN CY DE DK ES FI FR GB GR IE IT JP KG KZ LI LU MC MD MX NL NO PT RU SE TJ TM ZA

Title: ROBOTIC ORTHOSES FOR HAND AND WRIST REHABILITATION

Abstract: The robotic orthoses for rehabilitation of the hand and the wrist are a group of robotic orthoses designed for the passive and active rehabilitation of the fingers and the wrist, which consist in: A skin-orthosis interface formed by leather and neoprene parts to protect the patient's skin; a passive orthosis interface made of metal parts to couple the exoskeleton to the patient's wrist, fixed acrylic parts that act as a base for the structure, and mobile acrylic parts articulated by metal shafts to transmit movement to the hand and the wrist; an active orthosis interface made of servomotors that transmit movement to the mobile acrylic parts, reproducing 7 degrees of freedom to the movement of the hand and the wrist; and an electronic control module consisting of a switch-mode power supply, electronic boards and LED indicators.

Classifications:

International (IPC 8-9): A61F2/42 A61F5/00 A61F5/01 A61H1/00 A63B21/00 A63B23/00 A63B23/16 A63B24/00 (Advanced/Invention)



Family:

Publication number	Publication date	Application number	Application date
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WO18036571 A1	20180301	WO2017C000006	20170810

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Title: METHOD FOR **REHABILITATION** OF CONSEQUENCES OF neuroorthopedical (Machine translation)

Abstract: Source: UA107027U **Machine translation:** Method **rehabilitation** of patients with consequences neuroorthopedical pathology involves movement of the lower extremities using robotic systems "Lokomat". Treatment with the help of "Lokomat" is carried out in three phases - a preparatory stage, the stage of **passive** movement of the lower limbs and stage active-**passive** impact on the lower limbs; the preparatory stage of the pre-determined range of possible movements of the hip and knee joints of the extremities; patient record system robotic orthosis "Lokomat"; set by means of the regulation of the appropriate range of movement of joints; as the development of patient range of motion movements with the help of "Lokomat" gradually expand and conduct training to reduce muscle tone and achieve physiological indices range of movement of the joints of the extremities; the second stage first through **orthoses** of "Lokomat" set the maximum rate of discharge of the lower extremities; the patient is moved to a contact limb with treadmill; regulate the robotic **orthoses** so that they may do the right individual physiological walking pattern for the patient; carry out **passive** movements of the lower extremities using robotic **orthoses**, gradually increasing them load weight of the patient and the rate of **passive** walk to such values at which the lower limbs are the greatest possible proportion of the weight of his own body on adequate for the patient speed, at which the pattern of walking is correct; conduct training on these indicators to a conscious assimilation approximately patient simply

Classifications:

International (IPC 8-9): A61N1/32 (Advanced/Invention);
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