

Novel Electromechanic Artificial Urinary Sphincter

Sign In or Purchase
to View Full Text

3
Paper
Citations

218
Full
Text Views

Related Articles

H/sub /spl infin// Gaussian filter on infinite time horizon

Some future directions for repetitive pulsed power

[View All](#)

6

Author(s)

▼ Sami Hached ; ▼ Aref Trigui ; ▼ Oleg Loutochin ; ▼ André Garon ; ▼ Jacques Corcos ; ▼ Mohamad Sawan

[View All Authors](#)

Abstract

[Authors](#)

[Figures](#)

[References](#)

[Citations](#)

[Keywords](#)

[Metrics](#)

[Media](#)

Abstract:

Implantation of an artificial urinary sphincter (AUS) is the treatment of choice for managing severe stress urinary incontinence. This hydromechanical implant mimics a healthy sphincter by exerting a constant circumferential pressure around the urethra to close it and keep urine in the bladder. Common complications experienced with this device are urethral atrophy, erosion, and mechanical breakdown. Furthermore, AUS operation requires some dexterity resulting in difficulty and discomfort of use, and limiting the implantation in some patients. We present in this study a novel remote-controlled electromechanic AUS allowing rapid and effortless sphincter operation. Its design eliminates the classic manual pump, enhancing reliability, easing implantation in men and women, and achieving compatibility with already-implanted AUS. The device has been tested in vitro and ex vivo on fresh pig bladders. Different occlusive cuff pressure (OCP) ranges were employed and expected performance was obtained. Experimentation results and design challenges are reported and discussed here in.

Published in: [IEEE/ASME Transactions on Mechatronics](#) (Volume: 21, Issue: 2, April 2016)

Page(s): 945 - 955

INSPEC Accession Number: 15822991

Date of Publication: 12 October 2015 [?](#)

DOI: [10.1109/TMECH.2015.2490065](#)

▼ ISSN Information:

Print ISSN: 1083-4435

Electronic ISSN: 1941-014X

Publisher: IEEE

Sponsored by: [IEEE Industrial Electronics Society](#)
[ASME Dynamic Systems and Control Division](#)
[IEEE Robotics and Automation Society](#)