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END EFFECTOR FOR ROBOTIC SHOULDER ARTHROPLASTY

Abstract

A robotic surgical system can include an end effector coupled to a robotic arm. A reamer operable to ream bone can be coupled to the end effector (e.g., via a retainer). The reamer can include a primary driveshaft and a cutting head. The primary driveshaft can be rotatable about a first axis of rotation and the cutting head can be rotatable about a second axis of rotation, for example parallel to and offset from the first axis of rotation.

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Background/Summary

CLAIM OF PRIORITY [0001] This application is a divisional of U.S. patent application Ser. No. 17/224,841, filed on Apr. 7, 2021, which claims the benefit of U.S. Provisional Patent Application Ser. No. 63/015,217, filed on Apr. 24, 2020, the benefit of priority of each of which is claimed hereby, and each of which is incorporated by reference herein in its entirety.

BACKGROUND

[0002] During shoulder arthroplasty, a reamer or other cutting device can be used to shape a patient's bone surface, to prepare the bone to receive an implant. A reamer is typically guided by a guide pin. An incision is made in the shoulder region of a patient, into which the guide pin is inserted and affixed to the patient's bone surface. Cutting and shaping of the bone surface is then performed by rotating the reamer around the guide pin. A similar procedure can be utilized during replacement of other joints in the body, such to ream the acetabulum of a hip joint.

Description

BRIEF DESCRIPTION OF THE DRAWINGS

[0003] In the drawings, which are not necessarily drawn to scale, like numerals can describe similar components in different views. Like numerals having different letter suffixes can represent different instances of similar components. The drawings illustrate generally, by way of example, but not by way of limitation, various embodiments discussed in the present document.

[0004] FIG. 1A illustrates an isometric view of an end effector coupled to a robotic arm, in accordance with at least one example of the present application.

[0005] FIG. 1B illustrates an isometric view of a robotic arm, in accordance with at least one example of the present application.

[0006] FIG. 1C illustrates an isometric view of an end effector, in accordance with at least one example of the present application.

[0007] FIG. 2 illustrates an exploded view of an end effector, in accordance with at least one example of the present application.

[0008] FIG. 3 illustrates a side isometric view of a reamer, in accordance with at least one example of the present application.

[0009] FIG. 4 illustrates an isometric view of a retainer, in accordance with at least one example of the present application.

[0010] FIGS. 5A-5B illustrate side isometric views of a retainer and a collar, in accordance with at least one example of the present application.

[0011] FIG. 6 illustrates an isometric view of a retainer coupled to reamer, in accordance with at least one example of the present application.

[0012] FIG. 7 illustrates an isometric view of an end effector, in accordance with at least one example of the present application.

[0013] FIG. 8 illustrates an exploded view of an end effector, in accordance with at least one example of the present application.

[0014] FIG. 9 illustrates a method of robotically controlling a reamer, in accordance with one example of the present application.

[0015] FIG. 10 illustrates a schematic view of a robotic surgical system for robotically assisted reaming, in accordance with at least one example of the present application.

[0016] FIG. 11 illustrates a block diagram of an example machine upon which any one or more of

the techniques discussed herein can be performed, in accordance with at least one example of the present application.

DETAILED DESCRIPTION

[0017] The following description and the drawings sufficiently illustrate specific examples to enable those skilled in the art to practice them. Other examples can incorporate structural, process, or other changes. Portions and features of some examples can be included in, or substituted for, those of other examples. Examples set forth in the claims encompass all available equivalents of those claims.

[0018] A shoulder joint replacement procedure, or shoulder arthroplasty, can involve making an access incision in a shoulder region of a patient. A guide pin can then be inserted through the incision to contact a bone surface; and is then fixedly coupled to the bone surface of the patient. The guide pin can be used to guide reamers or other cutting instruments to a glenoid surface. Typically, cutting instruments used in shoulder arthroplasty include a rotatable cutting head that is used to cut and shape the humerus, and the glenoid surface, to receive an implant.

[0019] Traditional reamers or other rotary cutting instruments often also include a driveshaft operable to rotate the cutting head. The cutting head and the driveshaft generally rotate around a shared axis of rotation. The driveshaft can block a surgeon's view of the cutting head from a position directly above the cutting head. This can require the surgeon to view the targeted bone surface and the cutting head from a position to the side, or from a position offset from, the cutting instrument. In such a situation, the access incision must be large enough to allow for both the insertion of a guide pin, and also for a clear line of sight to the bone surface, generally adjacent the cutting head. Further, the cutting range of a reamer or cutting instrument can be limited to the area directly around, or adjacent to, the guide pin. If subsequent reaming is to be performed, the guide pin must be first removed and then reattached to bone in another area, further lengthening the surgical procedure and increasing the recovery time of a patient. Additionally, when the reamer is restricted to rotating around the guide pin, the reamer is limited to a single cutting angle or trajectory, because the guide pin attached to bone.

[0020] The systems and methods disclosed herein provide solutions to the technical problems identified above by providing for a reamer configured to be used with a robotic arm capable of precisely guiding the reaming of a bone. The reamer and the robotic arm can ream the bone within a less invasive incision, which reduces the length of shoulder replacement procedures and the recovery time of a patient. The end effector can include a reamer that can be guided by a robotic arm. The reamer can include a driveshaft and a cutting head, where the cutting head can be rotatable around a separate and offset axis of rotation relative to the driveshaft.

[0021] The robotic arm and the end effector can together eliminate the need for a guide pin. The offset reamer can reduce the size of an access incision by affording a surgeon a view from directly above a cutting head, eliminating the need for viewing a cutting head from the side. The robotic arm can articulate to precisely position the reamer to access a bone surface at a variety of different cutting angles or trajectories, for greater bone preservation. These benefits can together enable a surgeon to complete a shoulder joint replacement procedure using a smaller incision, and with improved accuracy and greater bone preservation, helping to provide improved outcomes for a patient, such as increased repeatability, a shorter hospital stay, and a reduced recovery time.

[0022] While the following examples are discussed in view of a shoulder arthroplasty procedure, the described robotic arm, end effector, and reamer can be utilized in other similar arthroplasty procedures. For example, the robot, end effector, and reamer can be utilized to ream an acetabulum during a hip arthroplasty procedure. The offset nature of the reaming, in combination with the robotic arm, can provide similar benefits in a hip arthroplasty procedure as described throughout for the shoulder arthroplasty.

[0023] FIG. 1A illustrates an isometric view of an end effector **100** coupled to a robotic arm **102**, in accordance with at least one example of the present application. FIG. 1B illustrates an isometric

view of a robotic arm **102**, in accordance with at least one example of the present application. FIG. **1C** illustrates an isometric view of the end effector **100**, in accordance with at least one example of the present application. Also shown in FIG. **1C** are a longitudinal axis **L1**, longitudinal axis **L2**, a first axis **A1**, and orientation indicators Proximal and Distal. FIGS. **1A-1C** are discussed below concurrently. The end effector **100** can be coupled to the robotic arm **102**. Robotic arm **120** can be a 6 degree-of-freedom (DOF) robot arm, such as the ROSA® robot from Medtech, a Zimmer Biomet Holdings, Inc. company.

[0024] The robotic arm **102** can be controlled by a surgeon with various control devices or systems. For example, a surgeon can use a control system (e.g., a controller that is processor-implemented based on machine-readable instructions, which when implemented cause the robotic arm to move automatically or to provide force assistance to surgeon-guided movement) to guide the robotic arm **102**. A surgeon can use anatomical imaging, such as displayed on a display screen **104**, to guide and position the robotic arm **102**. Anatomical imaging can be provided to the display screen **104** with various imaging sources, such as one or more cameras positioned on the end effector **100**, or intraoperative fluoroscopy, such as a C-arm. The robotic arm **102** can include two or more articulating joints **106** capable of pivoting, rotating, or both, to provide a surgeon with wide range of adjustment options.

[0025] The anatomical imaging, for example, can be imaging of internal patient anatomy within an incision **107**. The incision **107** can be made in a variety of positions on a patient. For example, in a shoulder arthroplasty procedure, the incision **107** can be made in a shoulder region of a patient. The incision **107** can be configured to allow the end effector **100**, coupled to the robotic arm **102**, to access a bone surface, or other anatomy of the patient. The end effector **100** can also include a base **108**, which can be configured to couple the end effector **100** to the robotic arm **102**. The end effector **100** can also include a retainer **110**.

[0026] As shown in FIG. **1B**, the robotic arm **102** can include a computing system **109**, which can also communicate with display screens **104** and a tracking system **111**. The tracking system **111** can be operated by the computing system **109** as a stand-alone unit. The computing system **109** can utilize the Polaris optical tracking system from Northern Digital, Inc. of Waterloo, Ontario, Canada. Additionally, the tracking system **111** can comprise the tracking system shown and described in Pub. No. US 2017/0312035, titled “Surgical System Having Assisted Navigation” to Brian M. May, which is hereby incorporated by this reference in its entirety. The tracking system **111** can monitor a plurality of tracking elements, such as tracking elements **113** and **115**. The tracking elements **113** and **115** can be affixed to objects of interest, to track locations of multiple objects within a surgical field.

[0027] The tracking system **111** can function to create a virtual three-dimensional coordinate system within the surgical field for tracking patient anatomy, surgical instruments, or portions of the end effector **100** or the robotic arm **102**. One or more of the tracking elements **113** and **115** can be tracking frames including multiple IR reflective tracking spheres, or similar optically tracked marker devices. In an example, one or more of the tracking elements **113** and **115** can be placed on or adjacent one or more bones of patient. In other examples, one or more of the tracking elements **113** and **115** can be placed on the end effector **100** or an implant to accurately track positions within the virtual coordinate system. In each instance, the tracking elements **113** and **115** can provide position data, such as a patient position, a bone position, a joint position, an implant position, a position of the robotic arm **102**, or the like.

[0028] As shown in FIG. **1C**, the retainer **110** of the end effector **100** can be comprised of a bar **112** and an arm **114**. The bar **112** and the arm **114** can generally be shafts having a square cross-sectional shape, but can also be shaped as round, rectangular, or the like. The retainer **110** can be solid or hollow. The bar **112** can extend along the longitudinal axis **L1**. The arm **114** can have portions which extend along the longitudinal axis **L2**. The arm **114** can have portions which extend at tangents to (or are not parallel with) the longitudinal axis **L1**; or can have portions which extend

perpendicular to the longitudinal axis L1. For example, the arm 114 can have portions which extend along longitudinal axis L2. Longitudinal axis L2 can be parallel with, but laterally offset from, longitudinal axis L1. The first axis A1 can be perpendicular to the longitudinal axis L1, or L2. The arm 114 of the retainer 110 can be C-shaped, U-shaped, V-shaped, or a variety of other shapes.

[0029] The end effector 100 can include a reamer 116, which can be configured to cut and shape a bone surface of a patient. The reamer 116 can include a primary housing 118. The primary housing 118 can include a proximal portion 120 and a distal portion 122. The primary housing 118 can be generally cylindrical in shape; but can also comprise other three-dimensional shapes such as rectangular prisms. The primary housing 118 can be coupled to the arm 114 of the retainer 110; to couple the reamer 116 to the retainer 110. The primary housing 118 can extend along the first axis A1. The reamer 116 can include a secondary housing 124 that can be generally cylindrical in shape; but can also comprise other three-dimensional shapes. The secondary housing 124 can extend orthogonally to the first axis A1; but can extend in other non-parallel orientations with respect to the first axis A1.

[0030] The reamer 116 can include a cutting head 126. The cutting head 126 can be a rotary cutting head configured to cut and shape bone via rotation. The cutting head 126 can be rotatably coupled to the secondary housing 124. As a result, the cutting head 126 can be vertically or laterally offset from the first axis A1 and the primary housing 118. The end effector 100 can include a motive source 128 that can be coupled to the proximal portion 120 of the primary housing 118. The motive source 128 can be an electrically actuated motor, a pneumatically operated motor, or other types of rotating drive sources. The motive source 128 can provide rotational drive to the cutting head 126 through the primary housing 118 and the secondary housing 124.

[0031] In the operation of some examples, the end effector 100 can be coupled to a robotic arm 102 in preparation for a surgical procedure. The surgical procedure can be a shoulder arthroplasty; but can also be other types of joint replacement procedures. A surgeon can make an incision 107 in a shoulder region of a patient. The robotic arm 102 can guide and position the end effector 100 to, and within, the incision 107. The cutting head 126, and other portions of the reamer 116, can be guided to a bone surface of a patient using the robotic arm 102 in a cooperatively-controlled mode utilizing robotic guidance. The motive source 128 can be selectively controlled to rotate the cutting head 126. The cutting head 126 can thereby be used to ream a bone surface of the patient, to shape the bone surface to receive an implant. In contrast to traditional methods using a fixed guide pin, the positioning of the end effector 100, including the cutting angle or trajectory of the reamer 116, can be easily adjusted intra-procedurally with the robotic arm 102.

[0032] The robotic arm 102 can provide a number of benefits to a patient. The end effector 100, with the robotic arm 102, can eliminate the need for a fixed guide pin in joint replacement procedures. The ability of the robotic arm 102 to be adjustably pivoted, rotated, or otherwise articulated intra-procedurally, either autonomously or cooperatively with the operator, to adjust the cutting angle or trajectory of the reamer 116 can allow for greater bone preservation than would be possible with a fixed guide pin. The robotic arm 102 can control the position, movement, and force applied by the cutting head 126 of the reamer 116 more precisely and steadily than a human hand, such that the cutting head 126 does not require a depth stop to prevent over-penetration of the cutting head 126 into a bone surface. This can reduce the cost of producing the reamer 116, and further decrease the amount of space needed within an incision for a cutting instrument to operate.

[0033] The cutting head 126 of the reamer 116 can be rotatable around a separate and offset axis of rotation relative to the motive source 128. The offset of the cutting head 126 can reduce the size of an access incision by affording a surgeon a view from directly above a cutting head, eliminating the need for viewing a cutting head from the side. These benefits can enable a surgeon to complete a shoulder joint replacement procedure with improved accuracy and greater bone preservation; and provide a patient with shorter hospital stay and a reduced recovery time.

[0034] FIG. 2 illustrates an exploded view of an end effector **100**, in accordance with at least one example of the present application. Also shown in FIG. 2 are orientation indicators Proximal and Distal relating to relative positions along the reamer **116**. As shown in FIG. 2, the secondary housing **124** can include a first portion **130** and a second portion **132** defining a bore **134**. The cutting head **126** can include a connector **136** and a cutting portion **138**. The arm **114** of the retainer **110** can include a proximal link **140**, a distal end **142**, and a coupler **144**. The bar **112** of the retainer **110** can include a proximal end **146**, a distal link **148**, and an extension **150**. The end effector **100** can also include a collar **152** and a channel **154**.

[0035] The first portion **130** and the second portion **132** can be generally opposite portions of the secondary housing **124** of the reamer **116**. The first portion **130** can be coupled to the distal portion **122** of the primary housing **118**. The second portion **132** can include the bore **134**. The cutting portion **138** can include cutting teeth, or other cutting or abrasive features. The cutting head **126** can form a generally cylindrical shape; but can also form other three-dimensional shapes. The connector can be configured to extend into, and engage the bore **134** of the secondary housing **124**, to couple the cutting head **126** to the reamer **116**.

[0036] The proximal link **140** and the distal end **142** can be generally opposite proximal and distal portions of the arm **114**. The arm **114** can include a coupler **144**. The coupler **144** can be positioned on, or can extend distally from, the distal end **142** of the arm **114**. The coupler **144** can be configured to releasably engage the primary housing **118**, to selectively couple the reamer **116** to the retainer **110** such that the primary housing **118** can be connected by the distal end **142** of the arm **114**. The coupler **144** can engage the primary housing **118**.

[0037] The distal link **148** of the bar **112** can be coupled to the proximal link **140** of the arm **114**. The retainer **110** can include the collar **152**. The collar **152** can be generally cylindrical in shape. The collar **152** can be configured to further secure the bar **112** to the arm **114**. The collar **152** can include the channel **154** that can be configured to accept, conform to, or encompass at least a portion of both the proximal link **140** and the distal link **148**. The collar **152** can thereby aid in coupling the bar **112** to the arm **114**, by encompassing portions of the proximal link **140** and the distal link **148**.

[0038] The bar **112** of the retainer **110** can include the extension **150**. The extension **150** can be a protrusion extending proximally from the proximal end **146**. The protrusion can be generally rectangular, cuboid, or cylindrical in shape, but can also comprise other three-dimensional shapes. The base **108** can include a bore **156**. The bore **156** can be configured to accept and engage the extension **150** to couple the retainer **110** to the base **108**. As the base **108** is configured to engage with a distal end of a robotic arm, such as the robotic arm **102** shown in FIG. 1A, the base **108** can couple the retainer **110** and the reamer **116** to a robotic arm.

[0039] FIG. 3 illustrates a side isometric view of a reamer **116**, in accordance with at least one example of the present application. Also shown in FIG. 3 is the first axis A1, a second axis A2, a third axis A3, and orientation indicators Proximal and Distal. As shown in FIG. 3, the reamer **116** can include a primary driveshaft **156**, (including a proximal shaft portion **158** and a distal shaft portion **160**), a secondary driveshaft **162**, a medial secondary portion **164**, a lateral secondary portion **166**, a first joint **168**, and a second joint **170**.

[0040] The primary driveshaft **156** can extend longitudinally along, and rotate around, the first axis A1. The primary driveshaft **156** can be configured to extend within the primary housing **118**. The proximal portion **158** of the primary driveshaft **156** can be coupled to the motive source **128**. The motive source **128** can thereby rotate the primary driveshaft **156** around the first axis A1 to rotate the primary driveshaft **156**.

[0041] The secondary housing **124** can extend along the second axis A2. The second axis A2 can be orthogonal to the first axis A1. In other examples, the second axis A2 can be not parallel with the first axis A1. The reamer **116** can include the secondary driveshaft **162**. The secondary driveshaft **162** can extend along, and rotate around, the second axis A2. The secondary driveshaft **162** can be

configured to extend within the secondary housing **124**, such that the secondary housing **124** can encompass the secondary driveshaft **162**.

[0042] The reamer **116** can also include the first joint **168** and the second joint **170**. The first joint **168** and the second joint **170** can be, for example, universal joints, but can also comprise a variety of other types of flexible joints or couplers. The first joint **168** can couple the distal portion **160** of the primary driveshaft **156** to the medial secondary portion **164** of the secondary driveshaft **162**. The second joint **170** can couple the lateral secondary portion **166** of the secondary driveshaft **162** to a connector of the cutting head **126**. The primary driveshaft **156** and the secondary driveshaft **162** can thereby rotatably couple the motive source **128** to the cutting head **126** while extending within the primary housing **118** and the secondary housing **124**. The cutting head **126** can extend along, and rotate around, the third axis **A3**. The third axis **A3** can extend parallel to, but laterally offset from, the first axis **A1**. In other examples, the third axis **A3** can be in other non-parallel orientations with respect to the first axis **A1**. As the primary driveshaft **156** is offset away from the cutting head **126**, a surgeon can view the cutting head **126** from a position directly above the cutting head **126**. This can provide the benefits of a smaller access incision and a less invasive procedure with a shorter recovery time for a patient.

[0043] FIG. **4** illustrates an isometric view of a retainer **110**, in accordance with at least one example of the present application. Also shown in FIG. **4** is a longitudinal axis **L1**, a longitudinal axis **L2**, a first axis **A1**, and orientation indicators Proximal and Distal. As shown in FIG. **4**, the arm **114** can include an offset segment **143**. The offset segment **143** can extend along the longitudinal axis **L2**. Longitudinal axis **L2** can be parallel with, but laterally offset from, longitudinal axis **L1**. The lateral offset of the offset segment **143** can allow the arm **114** of the retainer **110** to extend around various external anatomical features of a patient, in order to provide greater working space and positioning options for a surgeon, when using the end effector **100**. Other portions of the arm **114**, between the offset segment **143** and the proximal can extend at a tangent between the longitudinal axes **L1** and **L2**. The arm **114** of the retainer **110** can thereby be C-shaped, U-shaped, V-shaped, or a variety of other shapes.

[0044] The arm **114** of the retainer **110** can include the coupler **144**, which can be configured to couple the retainer **110** to the reamer **116**. The coupler **144** can include a first connector **172** and a second connector **174**. The first portion **172** and the second connector **174** can each be generally C-shaped couplers, but each can also form other three-dimensional shapes. The first connector **172** and the second connector **174** can extend distally from the distal portion **144**, along the longitudinal axis **L1**. The first connector **172** and the second connector **174** extend from the distal end **142** in a parallel orientation relative to each other. The coupler **144** can also include a protrusion **175**. The protrusion **175** can be generally cylindrically-shaped but can also comprise other three-dimensional shapes. The protrusion **175** can extend distally from one, or both, of the first connector **172** and the second connector **174**.

[0045] The protrusion **175** can be configured to engage the primary housing **118** of the reamer **116**, to further aid in securely retaining the primary housing **118** within the coupler **144**. The coupler **144**, including the protrusion **175**, can be configured to fixedly, or adjustably, couple the arm **114** to the primary housing **118**. For example, the coupler **144** can be configured to allow the primary housing **118** to slide proximally and distally along the first axis **A1**, within the coupler **144**. Alternatively, the coupler **144** can be configured to fixedly retain the primary housing **118** in certain situations, for example, when it is desirable to apply an increased force to the cutting head **126**.

[0046] FIGS. **5A-5B** illustrate side isometric views of a retainer **110** and a collar **152**, in accordance with at least one example of the present application. In FIG. **5A**, the collar **152** is shown in phantom. Also shown in FIGS. **5A-5B** are a longitudinal axis **L1**, and orientation indicators Proximal and Distal. FIGS. **5A** and **5B** are discussed below concurrently.

[0047] As shown in FIGS. **5A-5B**, the arm **114** of the retainer **110** can include a flange **176**. The

flange **176** can be protrusion extending outwardly from the proximal link **140** of the arm **114**. The flange **176** can be generally cuboid in shape, but can also be rectangular or other three-dimensional shapes. The flange **176** can extend vertically and laterally (e.g., radially) beyond a height and a width of the arm **114**. The flange **176** can be configured to limit distal travel of the collar **152**, such as when the collar **152** is positioned over at least a portion of the proximal link **140** of the arm **114**. [0048] The proximal link **140** of the arm **114** can include a body **178** and arms **180**. The body **178** can be a portion of the proximal link **140** having a reduced height and width, relative to dimensions of other portions of the arm **114**. The body **178** can extend along the longitudinal axis L1. The body **178** can generally be a shaft having a rectangular shape, or the like, but the body **178** can also form other three-dimensional shapes. The arms **180** can be protrusions or extensions extending orthogonally from the body **178**. The arms **180** can generally be a shaft having a cylindrical shape, but the arms **180** can also form other three-dimensional shapes.

[0049] The distal link **148** of the bar **112** can include a channel **182** and a recess **184**. The channel **182** can generally extend along, and through a distal end, of the distal link **148**. The channel **182** can extend within the distal link **148** along the longitudinal axis L1. The channel **182** can be configured to accept, contact, and retain the body **178** of the proximal link **140**. The recess **184** can extend within the distal link **148** orthogonally to the longitudinal axis L1. The recess **184** can be configured to accept, contact, and retain the arms **182** of the proximal coupler **178**.

[0050] As shown in FIG. 5B, the distal link **148** of the bar **112** can also include a first lock bore **186**. The lock bore **186** can extend transversely within the distal link **148**; orthogonally to the longitudinal axis A1. The collar **152** can include a first pin bore **188**. The first pin bore **188** can extend transversely within the collar **152**; orthogonally to the longitudinal axis A1. The first lock bore **186** and the first pin bore **188** can each be configured to accept, contact, and retain a first pin **190**. The first pin **190** can be a solid pin, a roll pin, or other types of generally cylindrical fasteners.

[0051] In the operation of at least one example, the collar **152** can be positioned around the first portion **112**. The distal link **148** of the bar **112** can engage the proximal link **140** of the arm **114**, to couple the bar **112** to the arm **114**. The collar **152** can slide distally over and along the bar **112** until the collar **152** contacts the flange **176**, such the first lock bore **186** is aligned with the first pin bore **188**. When the collar **152** contacts the flange **176**, the collar **152** can be in a position encompassing both the proximal link **140** of the arm **114** and the distal link **148** of the bar **112**, furthering securing the bar **112** to the arm **114** by helping to limit relative lateral or radial movement of the proximal coupler **178** and the distal link **148**, helping to prevent the proximal coupler **178** from disengaging the distal link **148**. The first pin **190** can be inserted through the first pin bore **188** in the collar **152** and through the first lock bore **186** in the distal link **148** to lock the collar **152** in position, which can help prevent the collar **152** from traveling proximally along the longitudinal axis A1.

[0052] FIG. 6 illustrates an isometric view of a retainer **110** and a base **108** of an end effector **100**, in accordance with at least one example of the present application. Also shown in FIG. 6 is a longitudinal axis L1, and orientation indicators Proximal and Distal. As shown in FIG. 6, the base **108** can include a second lock bore **192**. The second lock bore **192** can extend within the base **108**, orthogonally to the longitudinal axis L1. The extension **150**, which can extend from the proximal end **146** of the bar **112**, can include a second pin bore **194**. The second pin bore **194** can extend within the extension **150**; orthogonally to the longitudinal axis L1. The second lock bore **192** and the second pin bore **194** can each be configured to accept, contact, and retain a second pin **196**. The second pin **196** can be a solid pin, a roll pin, or other types of generally cylindrical fasteners.

[0053] In the operation of at least one example, the extension **150** of the bar **112** can be inserted into the bore **156** of the base **108**, such that the second lock bore **192** is aligned with the second pin bore **194**. The second pin **196** can then be inserted into the second lock bore **192** of the base **108** and the second pin bore **194** in the extension **150** to couple the bar **112** to the base **108**. As the base **108** is configured to engage with a distal end of a robotic arm, such as the robotic arm **102** shown in FIG. 1A, the base **108** can thereby couple the bar **112** to the robotic arm **102**.

[0054] The base **108**, the retainer **110**, the primary housing **118**, the secondary housing **124**, the collar **152**, the primary driveshaft **156**, the secondary driveshaft **162**, the first joint **170**, the second joint **172**, and the first **190** and the second **196** pins, can each be made from, in an example, plastics or composites. For example, the components listed above can be molded, or otherwise made from, ABS plastic. The base **108**, the retainer **110**, the primary housing **118**, the secondary housing **124**, the lock collar **152**, the primary driveshaft **156**, the secondary driveshaft **162**, the first joint **170**, the second joint **172**, and the first **190** and the second **196** pins, can also each be made from stainless steel, or other metals via machining or metallic molding.

[0055] FIG. 7 illustrates an isometric view of an end effector **200**, in accordance with at least one example of the present application. FIG. 8 illustrates an exploded view of an end effector **200**, in accordance with at least one example of the present application. Also shown in FIG. 7 is a first axis **A1**, a third axis **A3**, a longitudinal axis **L1**, and orientation indicators Proximal and Distal. FIGS. 7-8 are discussed below concurrently. The end effector **200** can include any of the components of the end effector **100** discussed and shown with regard to FIGS. 1A-6 above.

[0056] The end effector **200** can include a retainer **202** extending along the longitudinal axis **L1**. The retainer **202** can be similar to the retainer **114**, such as including the proximal link **140** or the offset segment **143**; and can be configured to engage with the bar **112**, or with the base **108** directly. The end effector **200** can include a reamer **204**. The reamer **204** can be similar to the reamer **116**, such as including the primary **118** and the secondary **162** driveshafts extending along the first axis **A1** and along the second axis **A2**, respectively, to enable the third axis **A3** of the cutting head **126** to be laterally offset from the first axis **A1** of the primary driveshaft **118**. In some examples, such as the end effector **200** shown in FIGS. 7-8, the reamer **204** can enable the orientation of the first axis **A1** to change relative to the orientation of the third axis **A3**. For example, a primary driveshaft **206** defining the first axis **A1** can be adjustable relative to a cutting head **208** defining the third axis **A3**. The primary driveshaft **206** can include a proximal shaft portion **210** and distal shaft portion **212**. The proximal shaft portion **210** can include a protrusion **214**. The protrusion **214** can be configured to engage with a drive source, such as the motive source **128**.

[0057] The distal shaft portion **212** can include a driver **216**. The driver **216** can be a feature formed on, or coupled to, the distal portion **212**. The driver **216** can generally be in the shape of a hexagonal or an octagonal prism; but can also form other three-dimensional shapes. The reamer can include a drive coupler **220**. The driver **216** can be configured to engage, such as by being positioned at least partially within, a head **218** of the drive coupler **220**. The head **218** can be a complimentary recess, relative to the shape of the driver **216**, formed in the drive coupler **220**. The drive coupler **220** can be coupled to the cutting head **208**, such via the coupler **136** shown in FIG. 2. The drive coupler **220** can thereby engage both the cutting head **208** and the driver **216** to transfer rotational motion from driveshaft **206** to the cutting head **208**. The driver **216** can securely engage the head **218** at a variety of angles relative to the drive coupler **220**, to thereby allow angulation of the primary driveshaft **206** relative to the cutting head **208**.

[0058] The reamer **204** can include a bushing **222**. The bushing **222** can generally be cylindrical in shape; and can include a bore **224**. The bore **224** can be configured to accept the drive coupler **220**, such to allow the drive coupler **220** to rotate within the bore **224** of the bushing **222**. The reamer **204** can further include a plurality of bearings **226**. The bearings **226** can be, for example, ball or needle bearings located within the bore **224**. The bearings **226** can be located between an outer surface of the drive coupler **220** and an inner surface of the bushing **222** defining the bore **224**. As such, the bushing **222** can function as an outer bearing race and the drive coupler **220** can function as an inner bearing race. The bearings **226** could also be a bushing or could include surfaces to promote articulation or rotation. The bearings **226** can thereby reduce friction between the bushing **222** and the drive coupler **220**.

[0059] The retainer **202** can include distal portion **226**. The distal portion **226** can include or otherwise form a housing **228**. The housing **228** can generally be cylinder in shape; and can be

configured to encompass and fixedly retain the bushing **222**. The end effector **200** can thereby enable the primary driveshaft **206** to be adjusted and angled relative to the cutting head **208**, independently of, or in addition to, the lateral offset between the first axis **A1** and the third axis **A3** shown in FIG. **3** above. This can enable a user to intra-procedurally adjust the orientation of the primary driveshaft, such as to improve the visibility of a target bone surface for a surgeon by moving the driveshaft out of the surgeon's line of sight.

[0060] FIG. **9** illustrates a method **300** of robotically controlling a reamer, in accordance with one example of the present application. The steps or operations of the method **300** are illustrated in a particular order for convenience and clarity; many of the discussed operations can be performed by multiple different actors, devices, or systems. It is understood that subsets of the operations discussed in the method **300** can be attributable to a single actor, device, or system and can be considered a separate standalone process or method.

[0061] The method **300** includes an operation **302** to control movement of a robotic arm to position an end effector at a distal end of the robotic arm within a glenoid cavity of a patient.

[0062] The method **300** includes an operation **304** to activate a reamer affixed to the end effector to ream a glenoid surface of the patient within the glenoid cavity along a trajectory. After operation **304**, the method **300** may proceed to optional operation **306** when a trajectory change is identified, or may proceed to operation **312**. Operation **304** may include activating a cutting head of the reamer (e.g., at a distal end of the reamer). The cutting head may be configured to rotate about an axis of rotation without requiring use of a guide pin in a bone (e.g., the glenoid surface). This axis of rotation may differ from an axis of rotation for a primary driveshaft (e.g., offset and parallel to the primary driveshaft axis of rotation).

[0063] The method **300** includes an optional operation **306** to identify a change to the trajectory. Identifying the change may include receiving an indication of a change, for example on a user interface. In another example, identifying the change may be based on a current depth of the reamer or a preoperative plan.

[0064] The method **300** includes an optional operation **308** to control movement of the robotic arm to reposition the end effector according to the changed trajectory.

[0065] The method **300** includes an optional operation **310** to cause the reamer to ream the glenoid surface at the changed trajectory.

[0066] The method **300** includes an operation **312** to prevent overreaming by the reamer, using the robotic arm. In an example, operation **312** may be occurring during any or all operations **302-310**. Operation **312** may include preventing overreaming based on a specified maximum depth. The specified maximum depth may be based on a diagnostic image of the glenoid surface. In an example, a diagnostic depth may be determined, which may then be automatically translated by processing circuitry to a frame of reference of the robotic arm based on a registration to a frame of reference of the diagnostic image.

[0067] FIG. **10** illustrates a schematic view of a robotic surgical system **400** for robotically assisted reaming, in accordance with at least one example of the present application. The robotic surgical system **400** includes a robotic surgical device **402**, which can include a robotic arm **404**, an end effector **406**, such as to attach or manipulate a reamer **408** with a cutting head **410**, or the like. The robotic arm **404** can be similar to the robotic arm **102** discussed above with respect to FIG. **1A**, in that robotic arm **404** can be a movable and articulatable robotic arm. The end effector **406** can be similar to the end effector **100** discussed with respect to FIGS. **1A-6** above. The robotic arm **404** can move autonomously in an example. In another example, the robotic arm **404** can provide a force assist to surgeon or user guided movements. In yet another example, a combination of autonomous movement and force assist movement can be performed by the robotic arm **404** (e.g., force assist for an initial movement, and autonomously moving a later movement). In an example, the robotic arm **404** can resist an applied force. For example, the robotic arm **404** can be programmed to stay within a particular range of locations or a particular position, move at a

particular speed (e.g., resist a higher speed by resisting force), or the like.

[0068] The robotic surgical device **402** can output or receive data from a controller **412**. The controller **412** can be implemented in processing circuitry (e.g., hardwired or a processor), a programable controller, such as a single or multi-board computer, a direct digital controller (DDC), a programable logic controller (PLC), a system on a chip, a mobile device (e.g., cell phone or tablet), a computer, or the like. In one example, the controller **412** can output information to a display screen **414**. The display screen **414** can retrieve and display information from an imaging camera. The imaging camera can be physically positioned on the robotic surgical device **402**, such as on the robotic arm **404**, the end effector **406**, or the reamer **408** (e.g., on or near the cutting head **410**, such as on housing of the cutting head **410**). In an example, the display screen **414** can be used to display a user interface **418**. In an example, the display screen **414** can be a touch screen display. In another example, user interface **418** on the display screen **414** can provide lights, buttons, or switches. A user can thereby interact with the display screen **414** and the user interface **418** to input control commands, which can be relayed to the robotic surgical device **402** through the controller **412** to control the robotic surgical device **402**. The robotic surgical system **400** can be used to perform all, or a portion of, a surgical procedure on a patient.

[0069] In the operation of some examples, a user can interact with the user interface **418** on the display screen **414** to power on the robotic surgical device **402**. Power can be indicated by a light, for example, on the user interface **418**, or on the robotic arm **404**. When the robotic surgical device **402** is powered on, the user can operate the robotic arm **404**, end effector **406**, and the reamer **408**, including cutting head **410**, by interacting with the display screen **414** and the user interface **418**.

[0070] The robotic surgical system **400** can be used to ream a target bone surface of a patient, for example to prepare the bone surface to receive an implant, with the cutting head **410** of the reamer **408**. In an example, a cutting angle or trajectory of the cutting head **410** can be changed intra-operatively, for example using the controller **412**, in contrast to non-adjustable methods of guiding reamers, such a guide pin fixed to the bone. The robotic arm **404** can thereby allow a user to respond to specific bone conditions of a patient, to significantly improve the amount of a patient's bone that can be preserved during a joint replacement procedure. The bone penetration depth of the cutting head **410** can be precisely controlled using the robotic arm **404**, in contrast to traditional hand-held reamers requiring a depth-stop, to prevent over-penetration.

[0071] The robotic surgical system **400** may be configured to use the reamer **408** to ream bone. The reamer **408** can be coupled to the end effector **406**. The reamer **408** can include a primary driveshaft configured, for example, to rotate about a first axis of rotation. The cutting head **410** can be coupled to a distal end of the primary driveshaft. In an example, the cutting head **410** is configured to rotate about a second axis of rotation. The second axis of rotation can be parallel to and laterally offset from the first axis of rotation. The robotic arm **404** can be configured to robotically prevent overreaming by the reamer. For example, the controller **412** can receive a maximum depth or a depth range, identify a current depth, and prevent further depth movement by the robotic arm **404** when the current depth is at, exceeds, or approaches the maximum depth or the depth range. The depth range or the maximum depth can be determined preoperatively during a planning stage, in an example. The robotic arm **404** can prevent overreaming using a camera or ultrasonic transducer affixed to an end of the reamer **408** (e.g., at or near the cutting head **410** or on a housing thereof). The cutting head **410** can be configured to rotate about an axis of rotation without requiring use of a guide pin in the reamed bone. The robotic arm **404** can be configured to resist movement of the robotic arm **404** (e.g., to prevent translation or rotation by the reamer **408**) from a force applied by a motor.

[0072] FIG. **11** illustrates a block diagram of an example machine **500** upon which any one or more of the techniques discussed herein can perform in accordance with some embodiments. In alternative embodiments, the machine **500** can operate as a standalone device or can be connected (e.g., networked) to other machines. In a networked deployment, the machine **500** can operate in

the capacity of a server machine, a client machine, or both in server-client network environments. In an example, the machine **500** can act as a peer machine in peer-to-peer (P2P) (or other distributed) network environment.

[0073] The machine **500** can be a personal computer (PC), a tablet PC, a set-top box (STB), a personal digital assistant (PDA), a mobile telephone, a web appliance, a network router, switch or bridge, or any machine capable of executing instructions (sequential or otherwise) that specify actions to be taken by that machine. Further, while only a single machine is illustrated, the term “machine” shall also be taken to include any collection of machines that individually or jointly execute a set (or multiple sets) of instructions to perform any one or more of the methodologies discussed herein, such as cloud computing, software as a service (SaaS), other computer cluster configurations.

[0074] Machine (e.g., computer system) **500** can include a hardware processor **502** (e.g., a central processing unit (CPU), a graphics processing unit (GPU), a hardware processor core, or any combination thereof), a main memory **504** and a static memory **506**, some or all of which can communicate with each other via an interlink (e.g., bus) **508**. The machine **500** can further include a display unit **510**, an alphanumeric input device **512** (e.g., a keyboard), and a user interface (UI) navigation device **514** (e.g., a mouse). In an example, the display unit **510**, input device **512** and UI navigation device **514** can be a touch screen display. The machine **500** can additionally include a storage device (e.g., drive unit) **516**, a signal generation device **518** (e.g., a speaker), a network interface device **520**, and one or more sensors **521**, such as a global positioning system (GPS) sensor, compass, accelerometer, or other sensors. The machine **500** can include an output controller **528**, such as a serial (e.g., Universal Serial Bus (USB), parallel, or other wired or wireless (e.g., infrared (IR), near field communication (NFC), etc.) connection to communicate or control one or more peripheral devices (e.g., a printer, card reader, etc.).

[0075] The storage device **516** can include a machine readable medium **522** on which is stored one or more sets of data structures or instructions **524** (e.g., software) embodying or utilized by any one or more of the techniques or functions described herein. The instructions **524** can also reside, completely or at least partially, within the main memory **504**, within static memory **506**, or within the hardware processor **502** during execution thereof by the machine **500**. In an example, one or any combination of the hardware processor **502**, the main memory **504**, the static memory **506**, or the storage device **516** can constitute machine readable media.

[0076] While the machine readable medium **522** is illustrated as a single medium, the term “machine readable medium” can include a single medium or multiple media (e.g., a centralized or distributed database, or associated caches and servers) configured to store the one or more instructions **524**. The term “machine readable medium” can include any medium that is capable of storing, encoding, or carrying instructions for execution by the machine **500** and that cause the machine **500** to perform any one or more of the techniques of the present disclosure, or that is capable of storing, encoding or carrying data structures used by or associated with such instructions. Non-limiting machine-readable medium examples can include solid-state memories, and optical and magnetic media.

[0077] The instructions **524** can further be transmitted or received over a communications network **526** using a transmission medium via the network interface device **520** utilizing any one of a number of transfer protocols (e.g., frame relay, internet protocol (IP), transmission control protocol (TCP), user datagram protocol (UDP), hypertext transfer protocol (HTTP), etc.). Example communication networks can include a local area network (LAN), a wide area network (WAN), a packet data network (e.g., the Internet), mobile telephone networks (e.g., cellular networks), Plain Old Telephone (POTS) networks, and wireless data networks (e.g., Institute of Electrical and Electronics Engineers (IEEE) 802.11 family of standards known as Wi-Fi®, IEEE 802.16 family of standards known as WiMax®, IEEE 802.15.4 family of standards, peer-to-peer (P2P) networks, among others. In an example, the network interface device **520** can include one or more physical

jacks (e.g., Ethernet, coaxial, or phone jacks) or one or more antennas to connect to the communications network 526. In an example, the network interface device 520 can include a plurality of antennas to wirelessly communicate using at least one of single-input multiple-output (SIMO), multiple-input multiple-output (MIMO), or multiple-input single-output (MISO) techniques. The term “transmission medium” shall be taken to include any intangible medium that is capable of storing, encoding or carrying instructions for execution by the machine 500, and includes digital or analog communications signals or other intangible medium to facilitate communication of such software.

[0078] While the end effector has been discussed with regard to shoulder arthroplasty, the end effector of the present disclosure can be used in surgical procedures in a wide range of anatomical applications including knee, ankle, hip, or elbow procedures. The use of a robotic arm, together with the end effector, can eliminate the need for a guide pin, which can reduce the invasiveness of a joint replacement procedure for a patient. The offset reamer can provide a surgeon with the ability to view a patient's anatomy from directly above a cutting head, eliminating the need for a large incision to view a cutting head from the side. The robotic arm can provide increased accuracy, articulation, and precision over a fixedly attached guide pin, which can increase patient bone preservation to reduce trauma. These benefits can enable a surgeon to complete a shoulder joint replacement procedure with greater accuracy than existing devices and methods, to provide improved outcomes for a patient, such as increased repeatability, a shorter hospital stay, and a reduced recovery time.

NOTES AND EXAMPLES

[0079] The following, non-limiting examples, detail certain aspects of the present subject matter to solve the challenges and provide the benefits discussed herein, among others.

[0080] Example 1 is a robotically controlled reamer, the reamer comprising: a primary driveshaft configured to rotate about a first axis of rotation via a motor; a cutting head coupled to a distal end of the primary driveshaft, the cutting head configured to rotate about a second axis of rotation, parallel to and laterally offset from the first axis of rotation, and a cutting depth of the cutting head controllable by a robotic arm.

[0081] In Example 2, the subject matter of Example 1 includes, wherein the cutting depth of the cutting head is controlled by limiting movement of the robotically controlled reamer to less than a preoperatively specified cutting depth.

[0082] Example 3 is a robotic surgical system comprising: a reamer operable to ream bone coupled to an end effector, the reamer comprising: a primary driveshaft configured to rotate about a first axis of rotation; a cutting head coupled to a distal end of the primary driveshaft, the cutting head configured to rotate about a second axis of rotation, parallel to and laterally offset from the first axis of rotation; and a robotic arm including the end effector, the robotic arm configured to control a cutting depth of the cutting head.

[0083] In Example 4, the subject matter of Example 3 includes, wherein the robotic arm is configured to control the cutting depth of the cutting head by controlling movement of the reamer within a specified cutting depth range, the specified cutting depth range identified via preoperative planning.

[0084] In Example 5, the subject matter of Examples 3-4 includes, wherein the robotic arm is configured to control the cutting depth of the cutting head by using a camera affixed to the cutting head.

[0085] In Example 6, the subject matter of Examples 3-5 includes, wherein the cutting head is configured to rotate about the second axis of rotation without requiring use of a guide pin in the reamed bone.

[0086] In Example 7, the subject matter of Examples 3-6 includes, wherein the robotic arm is further configured to resist movement of the robotic arm from torque applied by the motor.

[0087] Example 8 is a reamer for shaping a bone without requiring a guide pin, the reamer

comprising: a primary driveshaft configured to rotate about a first axis of rotation; a cutting head coupled to a distal end of the primary driveshaft, the cutting head configured to rotate about a second axis of rotation laterally offset from the first axis of rotation.

[0088] In Example 9, the subject matter of Example 8 includes, wherein the second axis of rotation is parallel to the first axis of rotation.

[0089] In Example 10, the subject matter of Examples 8-9 includes, wherein the orientation of the primary driveshaft is adjustable relative to the orientation of the cutting head, such that the first axis of rotation is located at an acute or an oblique angle relative to the second axis of rotation.

[0090] In Example 11, the subject matter of Examples 8-10 includes, a motive coupler coupled to the primary driveshaft, the motive coupler engageable with a motive source to provide rotary motion to the primary driveshaft, at least a portion of the motive coupler and the primary driveshaft rotatable about the first axis of rotation.

[0091] In Example 12, the subject matter of Example 11 includes, wherein the motive source is an electric motor, the motor operable to rotate the primary driveshaft to rotate the cutting head.

[0092] In Example 13, the subject matter of Examples 11-12 includes, wherein the motive source is a pneumatically-actuated motor, the motor operable to rotate the primary driveshaft to rotate the cutting head.

[0093] In Example 14, the subject matter of Examples 8-13 includes, a retainer connecting the primary driveshaft to an end effector of a robotic arm, a portion of the retainer being laterally offset from both the end effector and the reamer.

[0094] In Example 15, the subject matter of Examples 8-14 includes, a secondary driveshaft coupled to the cutting head, the secondary driveshaft rotatable about a third axis of rotation that is not parallel to the first axis of rotation or the second axis of rotation.

[0095] In Example 16, the subject matter of Examples 8-15 includes, a camera coupled to a distal portion of a housing of the primary driveshaft.

[0096] Example 17 is a method of robotically controlling a reamer comprising: using processing circuitry, controlling movement of a robotic arm to position an end effector at a distal end of the robotic arm within a glenoid cavity of a patient; activating a reamer affixed to the end effector to ream a glenoid surface of the patient within the glenoid cavity along a trajectory; identifying a change to the trajectory; controlling, using the processing circuitry, movement of the robotic arm to reposition the end effector according to the changed trajectory; and causing the reamer to ream the glenoid surface at the changed trajectory.

[0097] In Example 18, the subject matter of Example 17 includes, wherein the change to the trajectory is received via a user interface.

[0098] In Example 19, the subject matter of Example 18 includes, wherein the change to the trajectory is determined automatically based on a preoperative plan.

[0099] Example 20 is a method of robotically controlling a reamer comprising: using processing circuitry, controlling movement of a robotic arm to position an end effector at a distal end of the robotic arm within a glenoid cavity of a patient; activating a reamer affixed to the end effector to ream a glenoid surface of the patient within the glenoid cavity along a trajectory; and controlling a cutting depth of the reamer, using the robotic arm, based on a specified maximum cutting depth.

[0100] In Example 21, the subject matter of Example 20 includes, wherein the maximum cutting depth is determined preoperatively based on a diagnostic image of the glenoid surface and automatically translated by the processing circuitry to a frame of reference of the robotic arm based on a registration to a frame of reference of the diagnostic image.

[0101] In Example 22, the subject matter of Examples 20-21 includes, wherein activating the reamer includes activating a cutting head of the reamer.

[0102] In Example 23, the subject matter of Example 22 includes, wherein activating the cutting head includes controlling a motor to rotate the cutting head about an axis of rotation without requiring use of a guide pin in the glenoid surface.

[0103] Example 24 is at least one machine-readable medium including instructions that, when executed by processing circuitry, cause the processing circuitry to perform operations to implement any of Examples 1-23.

[0104] Example 25 is an apparatus comprising means to implement any of Examples 1-23.

[0105] Example 26 is a system to implement any of Examples 1-23.

[0106] Example 27 is a method to implement any of Examples 1-23.

Claims

1. A robotically controlled reamer, the reamer comprising: a primary driveshaft configured to rotate about a first axis of rotation via a motor; a cutting head coupled to a distal end of the primary driveshaft, the cutting head configured to rotate about a second axis of rotation, parallel to and laterally offset from the first axis of rotation, and a cutting depth of the cutting head controllable by a robotic arm.
2. The robotically controlled reamer of claim 1, wherein the cutting depth of the cutting head is controlled by limiting movement of the robotically controlled reamer to less than a preoperatively specified cutting depth.
3. A robotic surgical system comprising: a reamer operable to ream bone coupled to an end effector, the reamer comprising: a primary driveshaft configured to rotate about a first axis of rotation; a cutting head coupled to a distal end of the primary driveshaft, the cutting head configured to rotate about a second axis of rotation, parallel to and laterally offset from the first axis of rotation; and a robotic arm including the end effector, the robotic arm configured to control a cutting depth of the cutting head.
4. The robotic surgical system of claim 3, wherein the robotic arm is configured to control the cutting depth of the cutting head by controlling movement of the reamer within a specified cutting depth range, the specified cutting depth range identified via preoperative planning.
5. The robotic surgical system of claim 3, wherein the robotic arm is configured to control the cutting depth of the cutting head by using a camera affixed to the cutting head.
6. The robotic surgical system of claim 3, wherein the cutting head is configured to rotate about the second axis of rotation without requiring use of a guide pin in the reamed bone.
7. The robotic surgical system of claim 3, wherein the robotic arm is further configured to resist movement of the robotic arm from torque applied by the motor.
8. A reamer for shaping a bone without requiring a guide pin, the reamer comprising: a primary driveshaft configured to rotate about a first axis of rotation; a cutting head coupled to a distal end of the primary driveshaft, the cutting head configured to rotate about a second axis of rotation laterally offset from the first axis of rotation.
9. The reamer of claim 8, wherein the second axis of rotation is parallel to the first axis of rotation.
10. The reamer of claim 8, wherein the orientation of the primary driveshaft is adjustable relative to the orientation of the cutting head, such that the first axis of rotation is located at an acute or an oblique angle relative to the second axis of rotation.
11. The reamer of claim 8, further comprising a motive coupler coupled to the primary driveshaft, the motive coupler engageable with a motive source to provide rotary motion to the primary driveshaft, at least a portion of the motive coupler and the primary driveshaft rotatable about the first axis of rotation.
12. The reamer of claim 11, wherein the motive source is an electric motor, the motor operable to rotate the primary driveshaft to rotate the cutting head.
13. The reamer of claim 11, wherein the motive source is a pneumatically-actuated motor, the motor operable to rotate the primary driveshaft to rotate the cutting head.
14. The reamer of claim 8, further comprising a retainer connecting the primary driveshaft to an end effector of a robotic arm, a portion of the retainer being laterally offset from both the end

effector and the reamer.

15. The reamer of claim 8, further comprising a secondary driveshaft coupled to the cutting head, the secondary driveshaft rotatable about a third axis of rotation that is not parallel to the first axis of rotation or the second axis of rotation.

16. The reamer of claim 8, further comprising a camera coupled to a distal portion of a housing of the primary driveshaft.

17. A method of robotically controlling a reamer comprising: using processing circuitry, controlling movement of a robotic arm to position an end effector at a distal end of the robotic arm within a glenoid cavity of a patient; activating a reamer affixed to the end effector to ream a glenoid surface of the patient within the glenoid cavity along a trajectory; identifying a change to the trajectory; controlling, using the processing circuitry, movement of the robotic arm to reposition the end effector according to the changed trajectory; and causing the reamer to ream the glenoid surface at the changed trajectory.

18. The method of claim 17, wherein the change to the trajectory is received via a user interface.

19. The method of claim 18, wherein the change to the trajectory is determined automatically based on a preoperative plan.

20. A method of robotically controlling a reamer comprising: using processing circuitry, controlling movement of a robotic arm to position an end effector at a distal end of the robotic arm within a glenoid cavity of a patient; activating a reamer affixed to the end effector to ream a glenoid surface of the patient within the glenoid cavity along a trajectory; and controlling a cutting depth of the reamer, using the robotic arm, based on a specified maximum cutting depth.

21. The method of claim 20, wherein the maximum cutting depth is determined preoperatively based on a diagnostic image of the glenoid surface and automatically translated by the processing circuitry to a frame of reference of the robotic arm based on a registration to a frame of reference of the diagnostic image.

22. The method of claim 20, wherein activating the reamer includes activating a cutting head of the reamer.

23. The method of claim 22, wherein activating the cutting head includes controlling a motor to rotate the cutting head about an axis of rotation without requiring use of a guide pin in the glenoid surface.
