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(54) **MAGNET MANAGEMENT MRI  
COMPATIBILITY**

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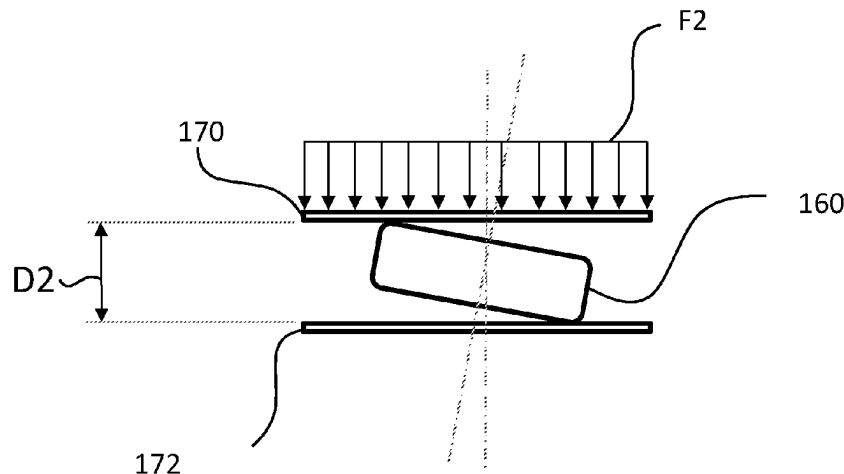
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(57) **ABSTRACT**

An implantable medical device, including a magnet and a  
body encompassing the magnet, wherein the implantable  
medical device includes structural components in the body  
configured to move away from one another upon initial  
rotation of the magnet relative to the body when the magnet  
is subjected to an externally generated magnetic field,  
thereby limiting rotation of the magnet beyond the initial  
rotation.

**30 Claims, 57 Drawing Sheets**



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FIG. 1A

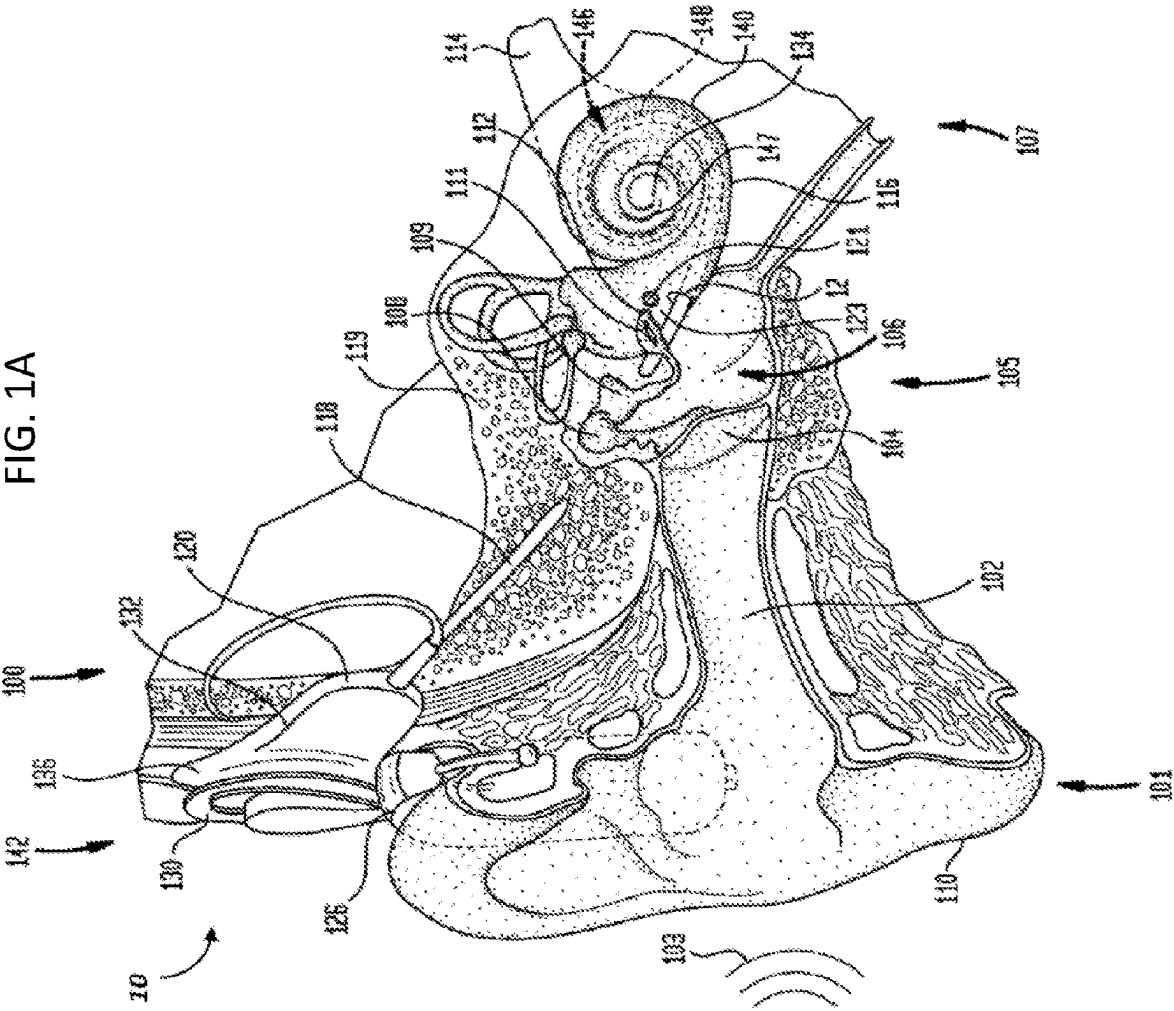


FIG. 1B

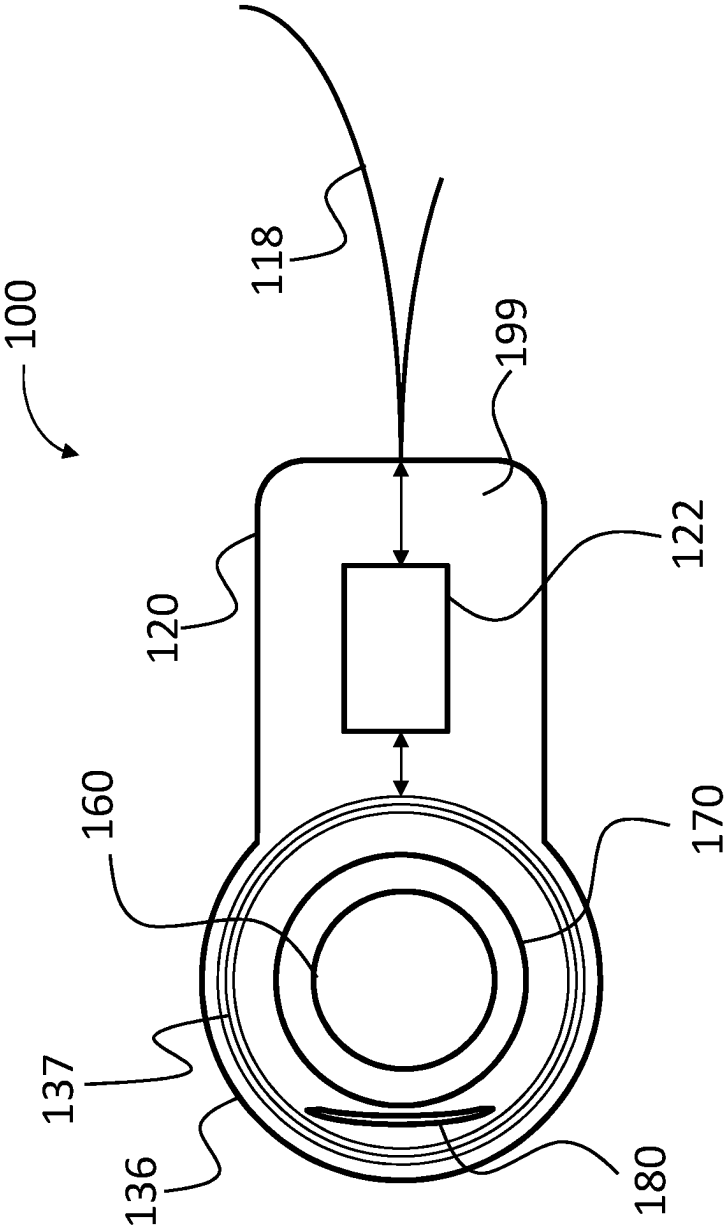


FIG. 1C

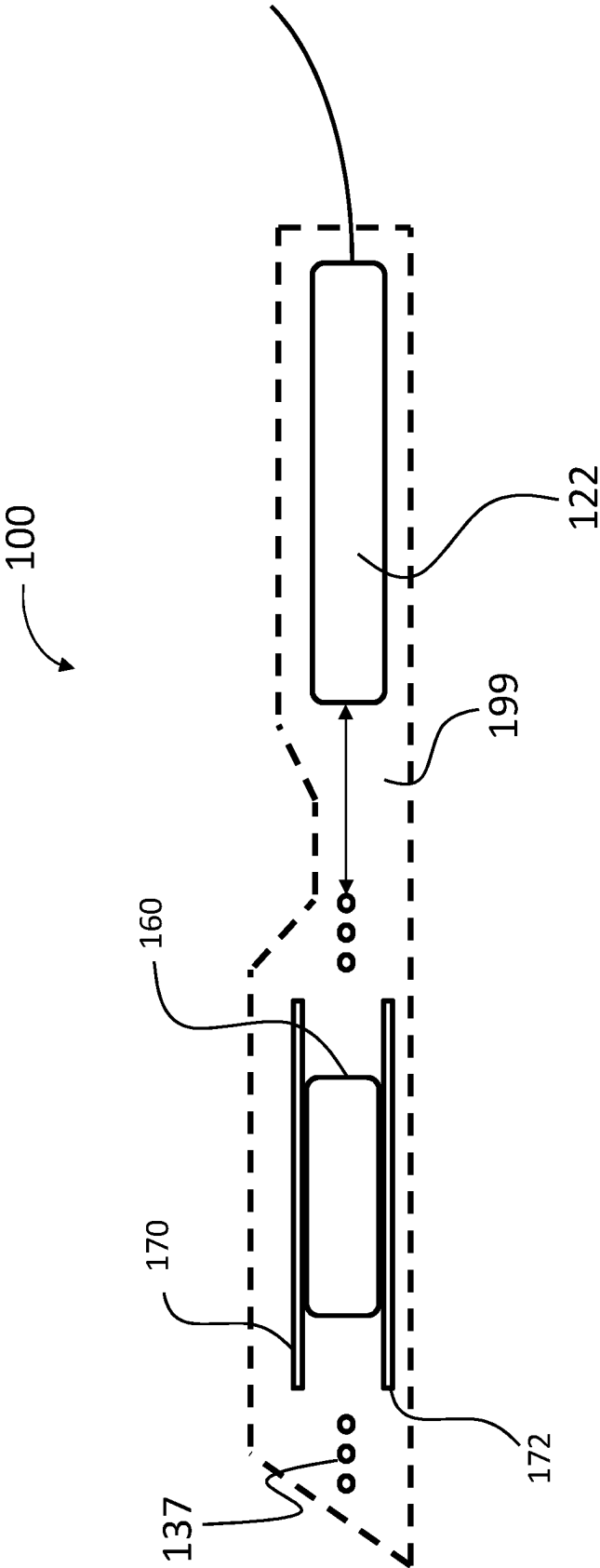




FIG. 2A

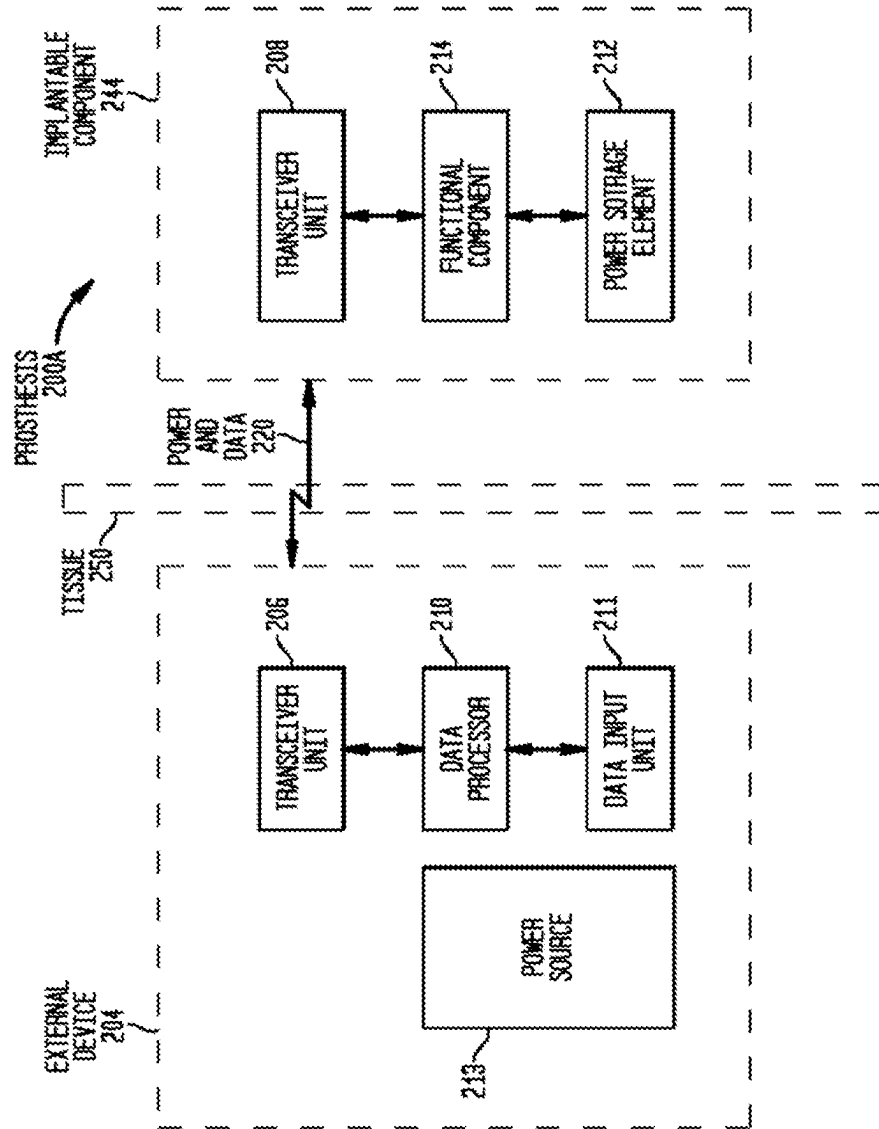


FIG. 2B

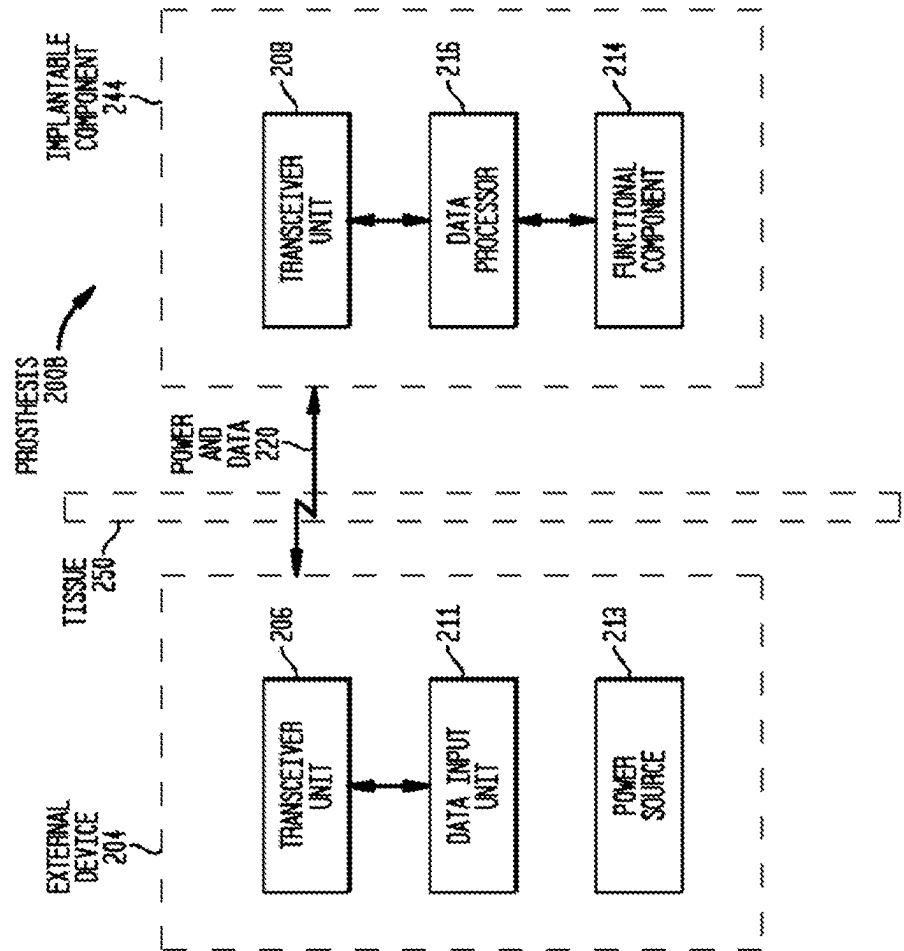


FIG. 3A

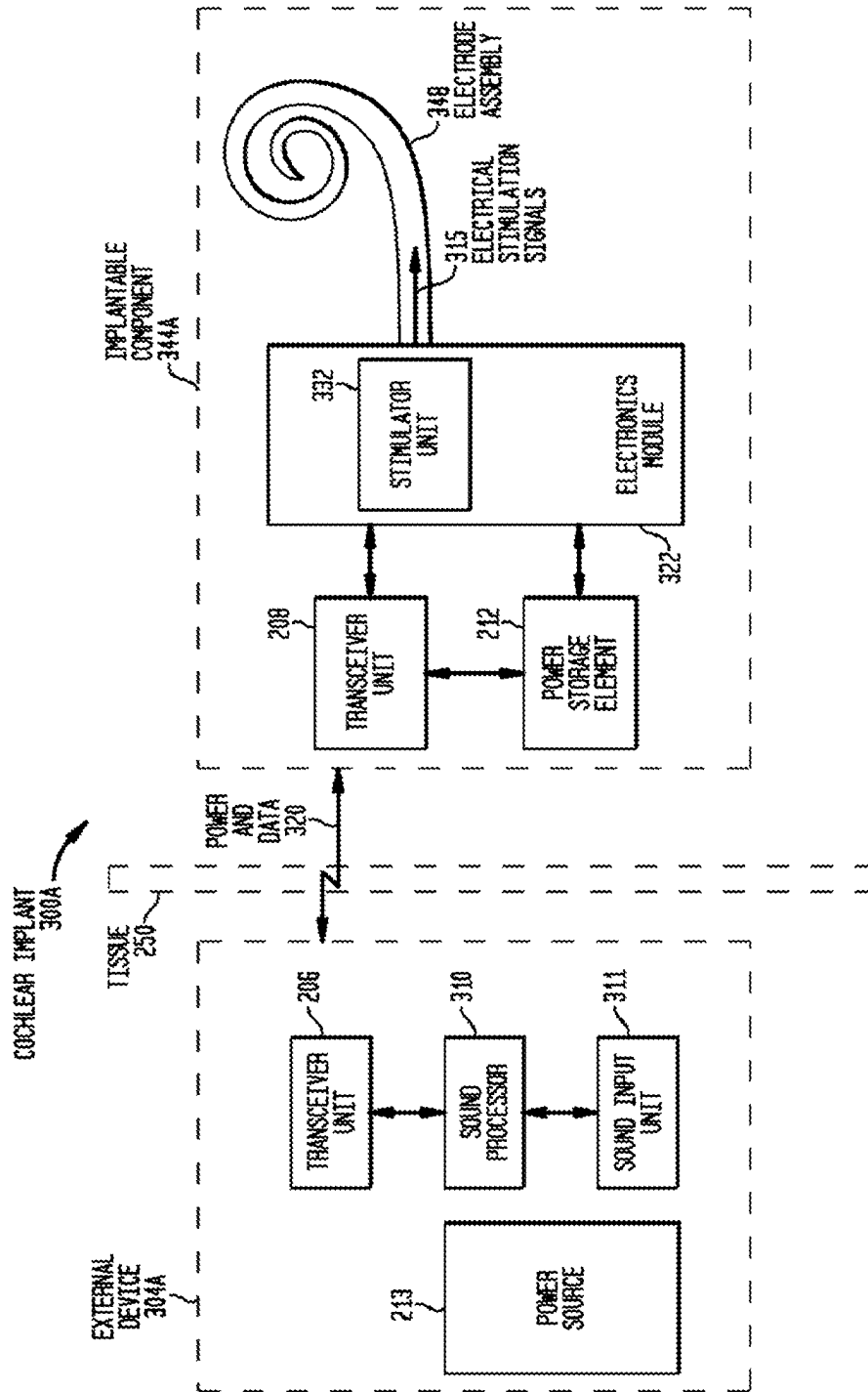


FIG. 3B

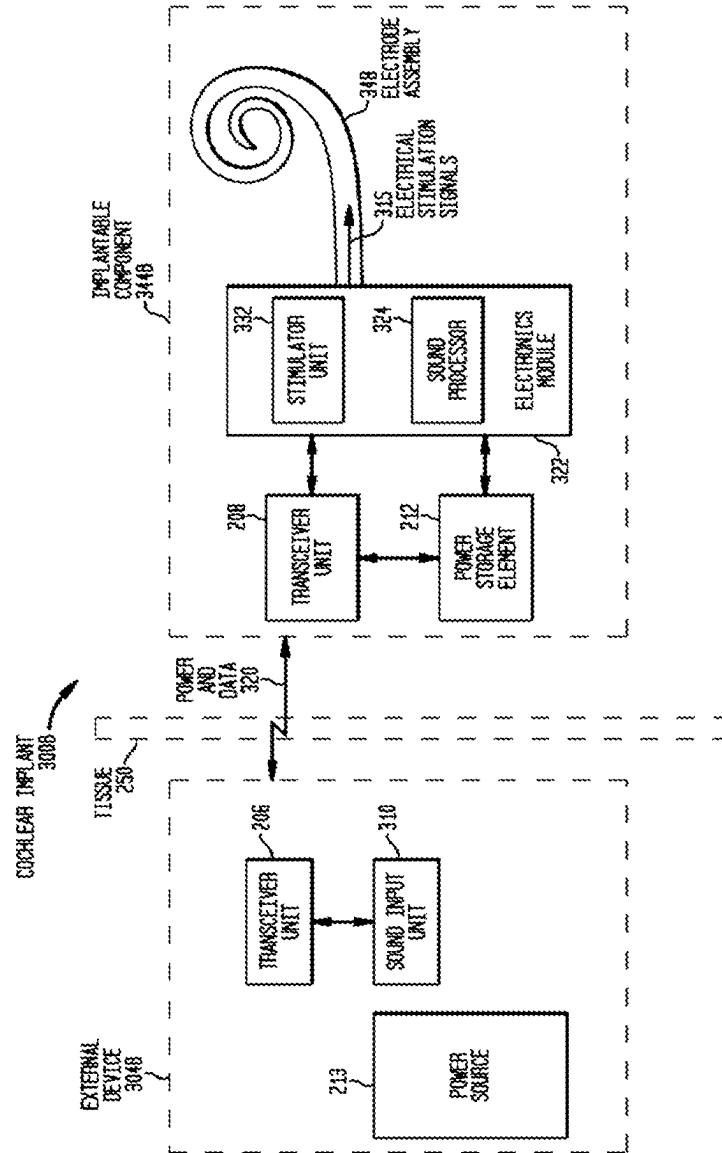


FIG. 3C

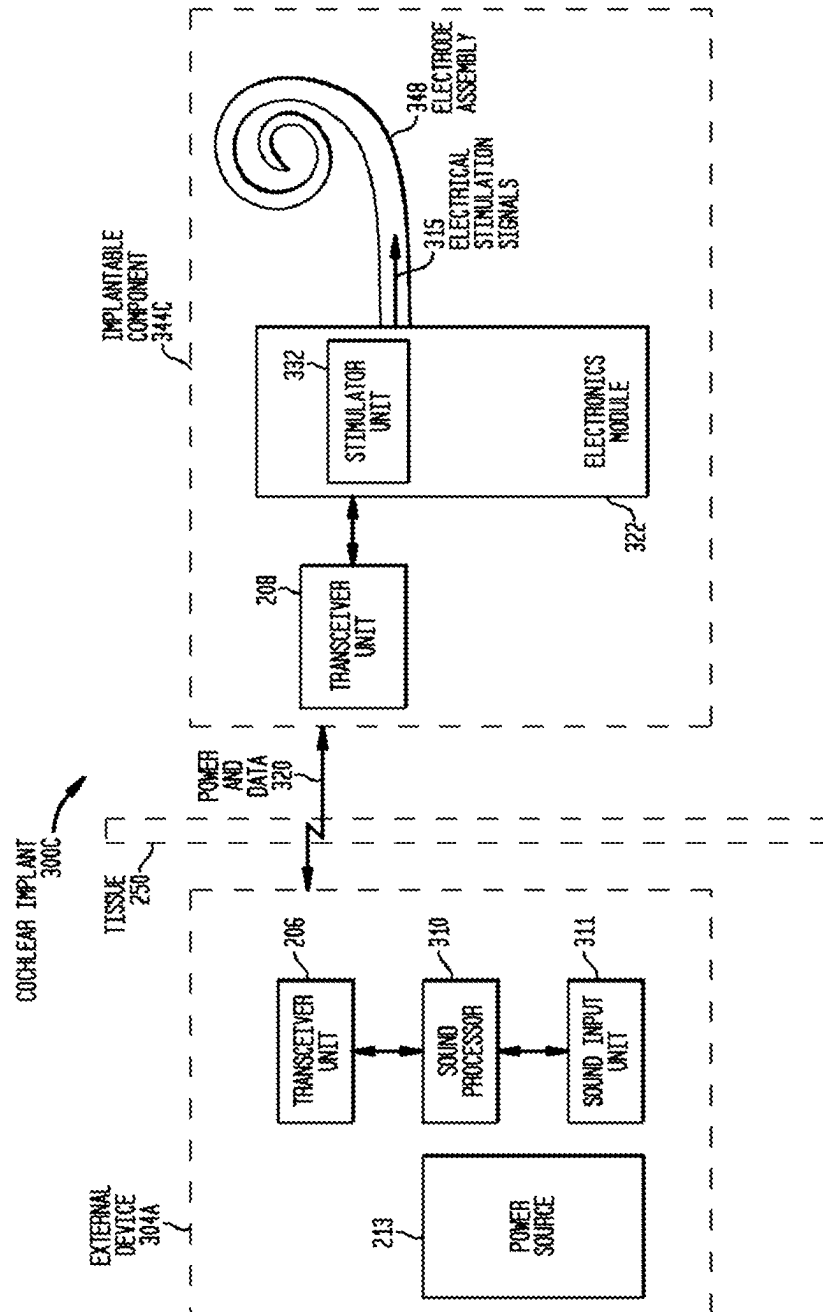


FIG. 4A

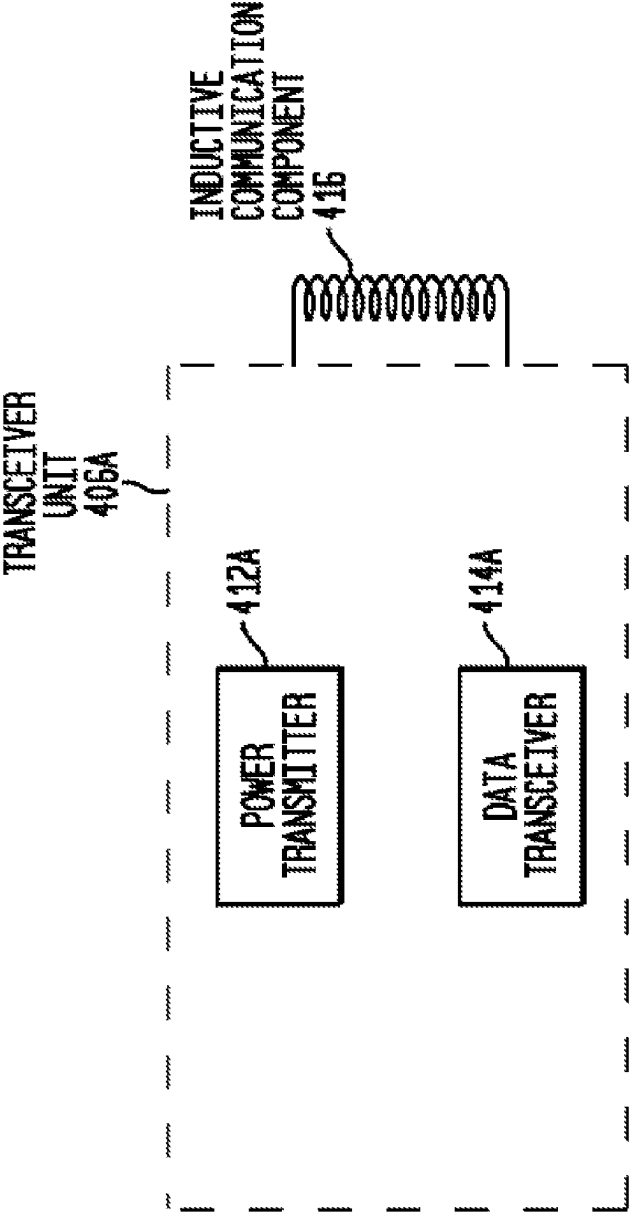
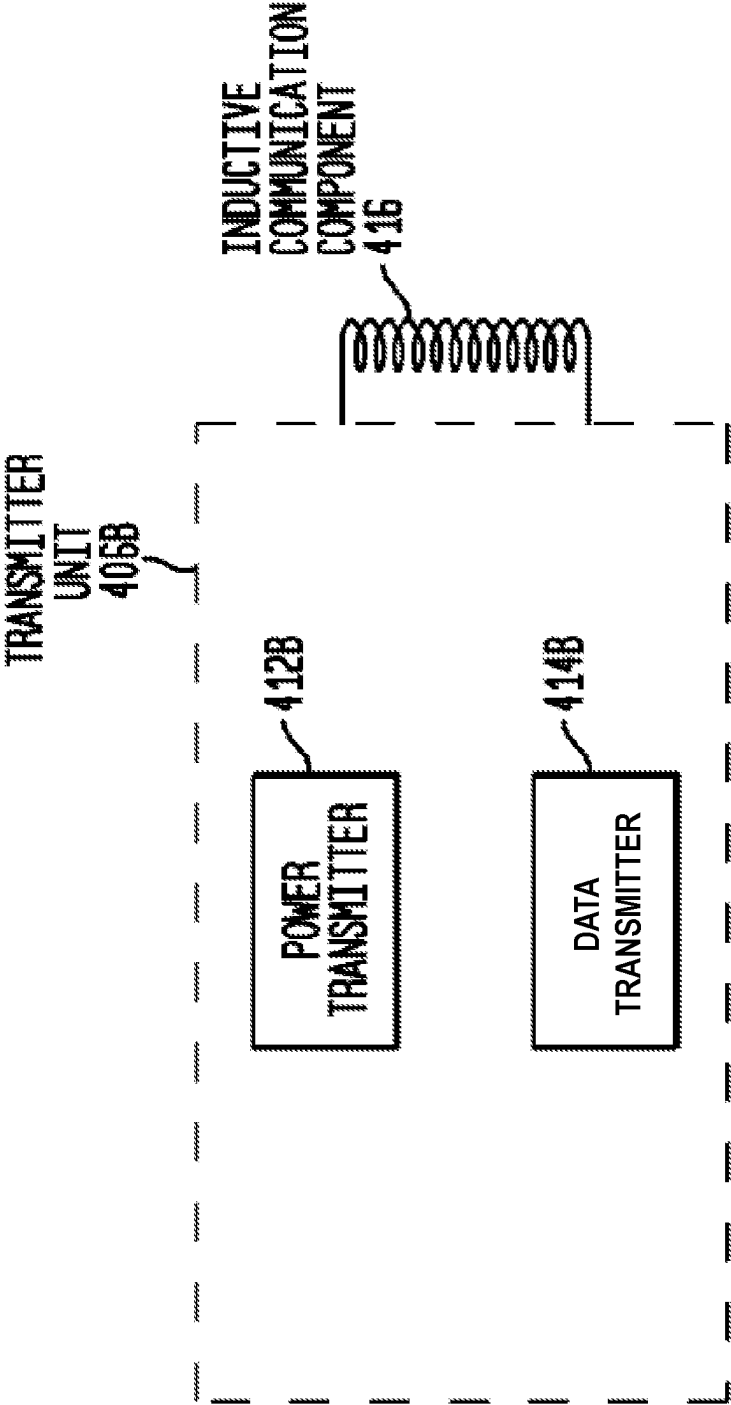


FIG. 4B



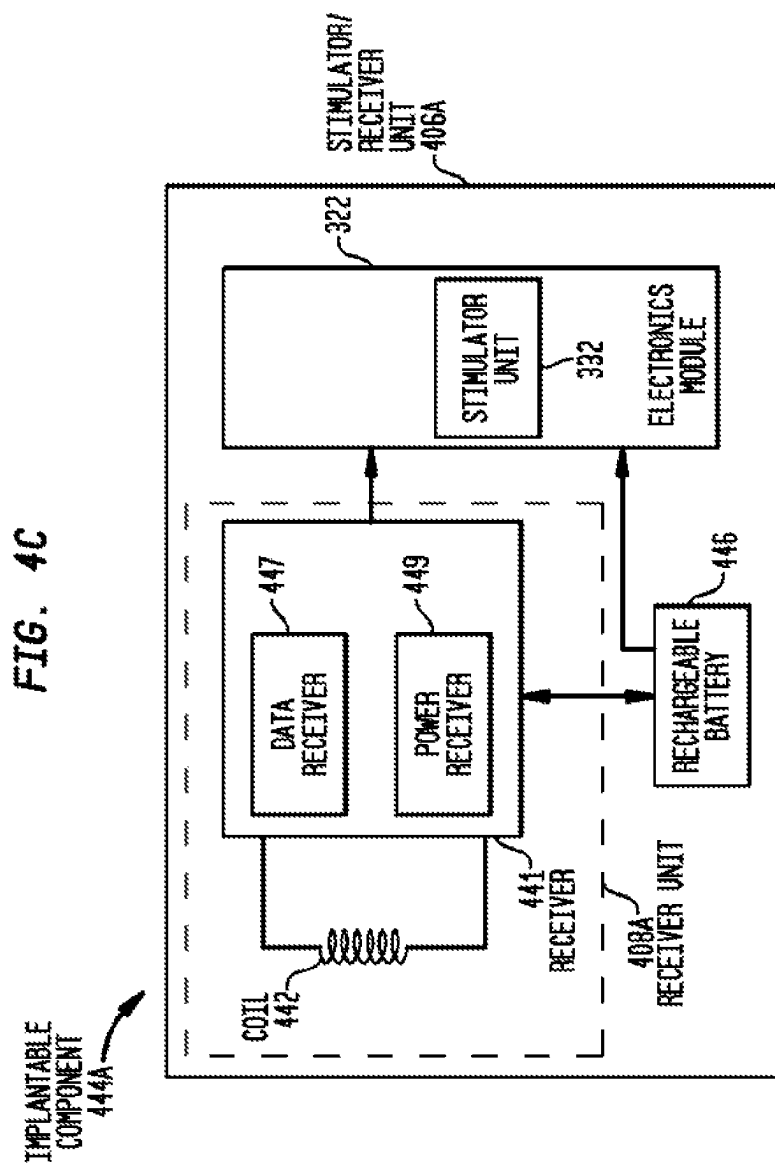
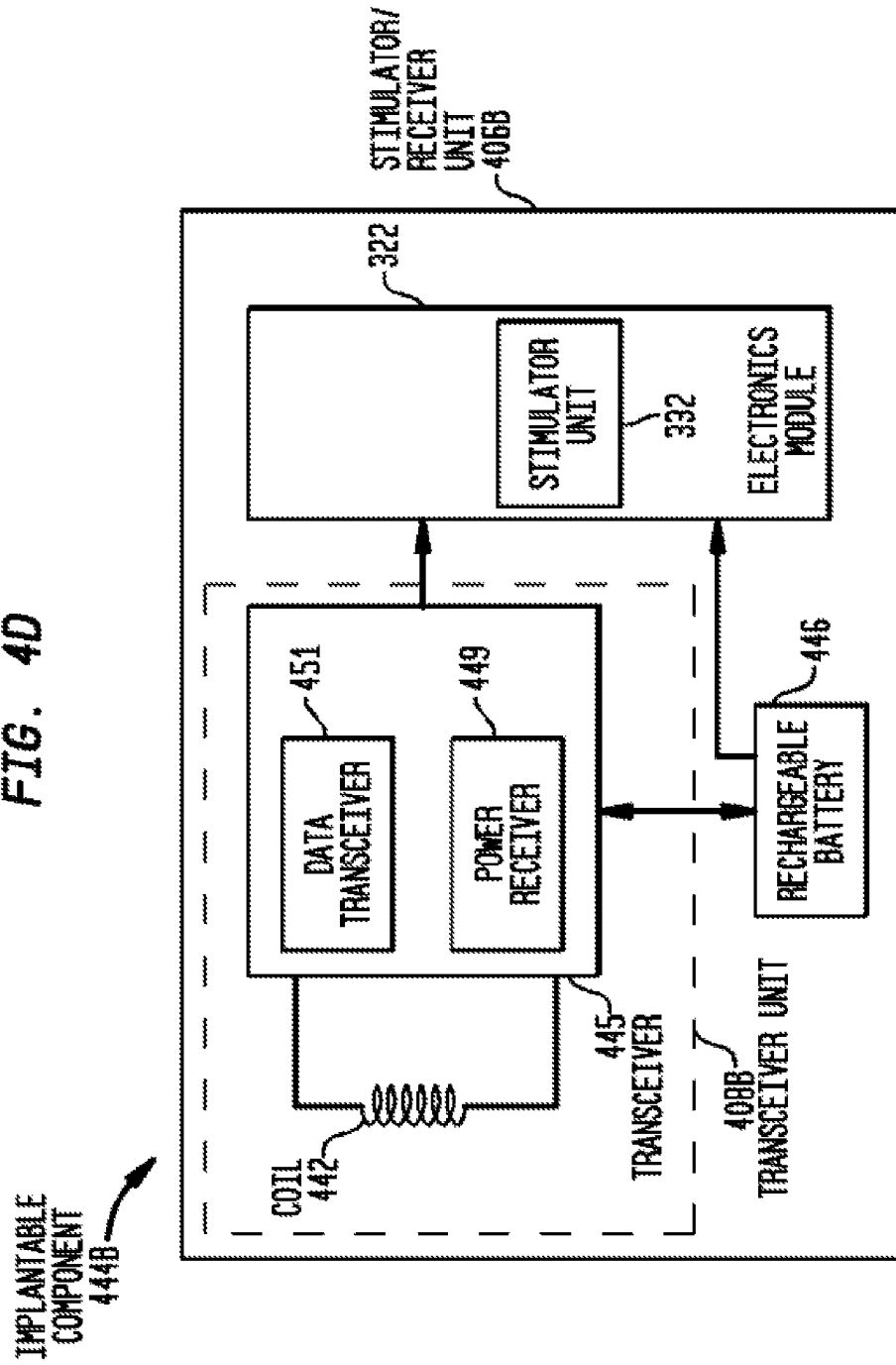
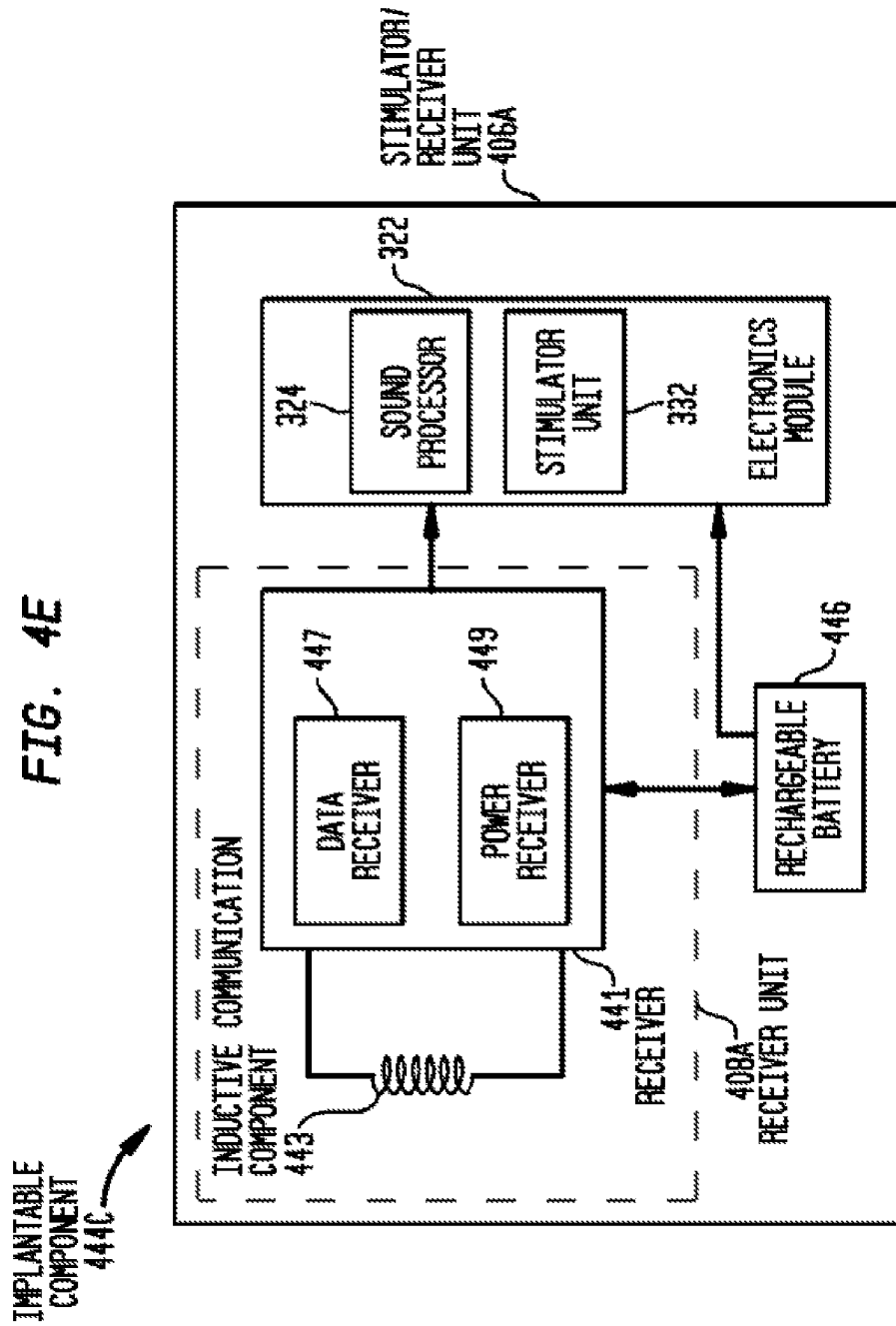




FIG. 4D





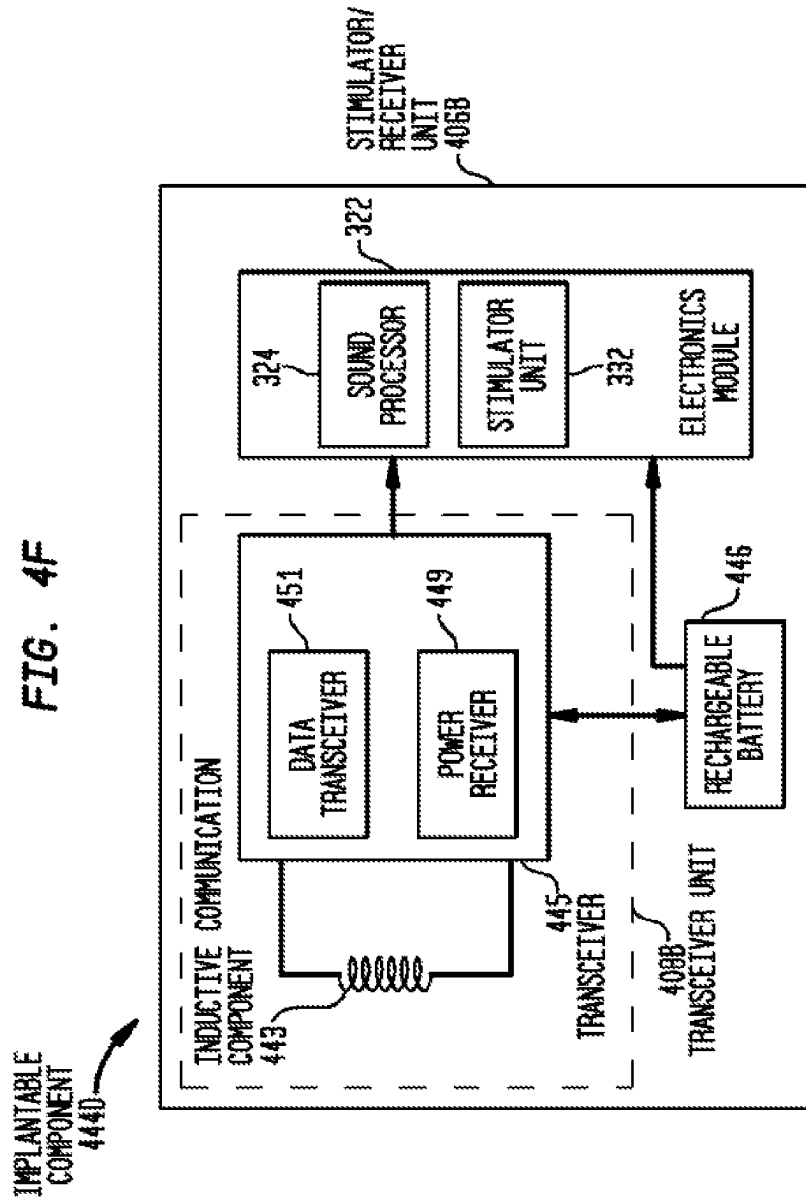


FIG. 5

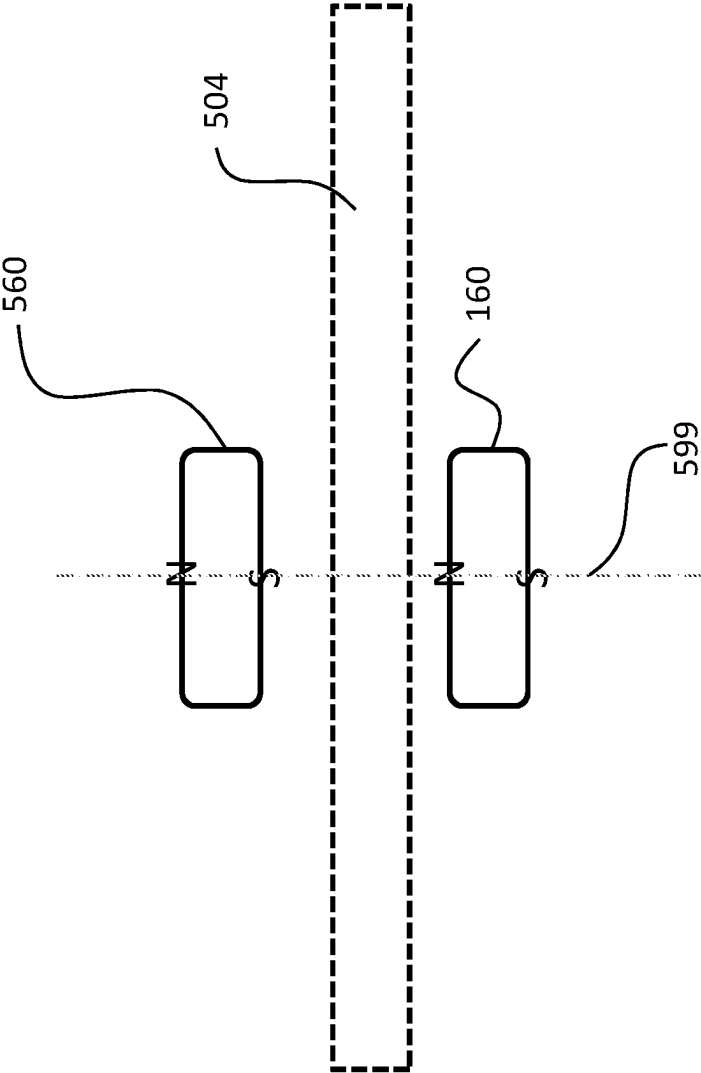


FIG. 6

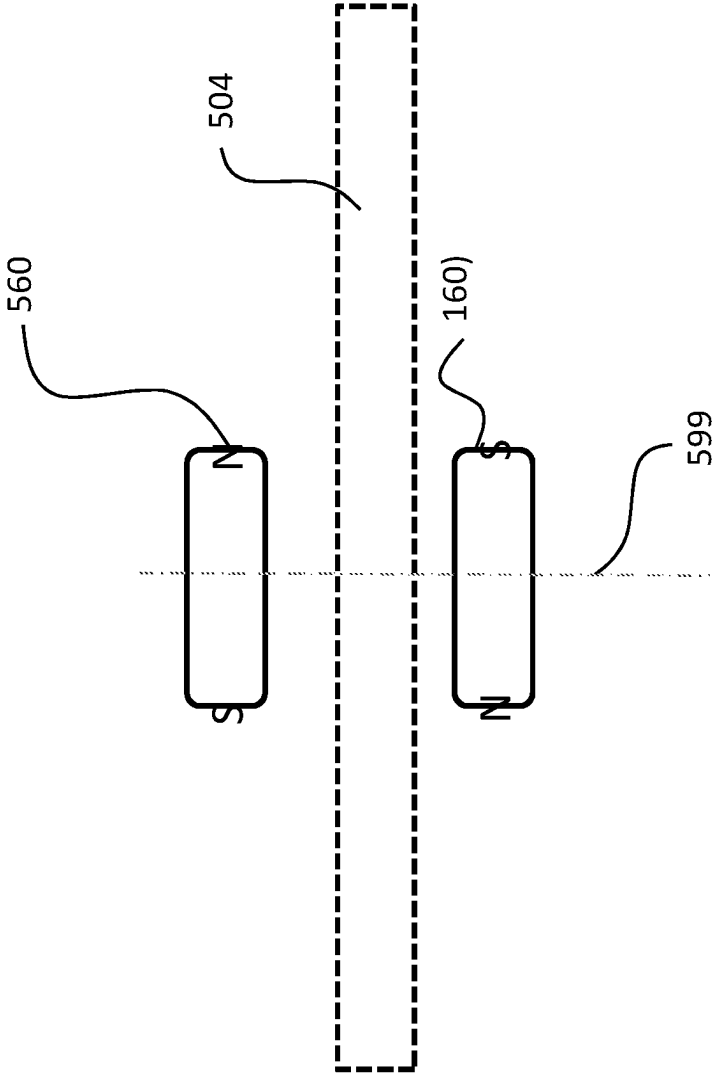


FIG. 7A

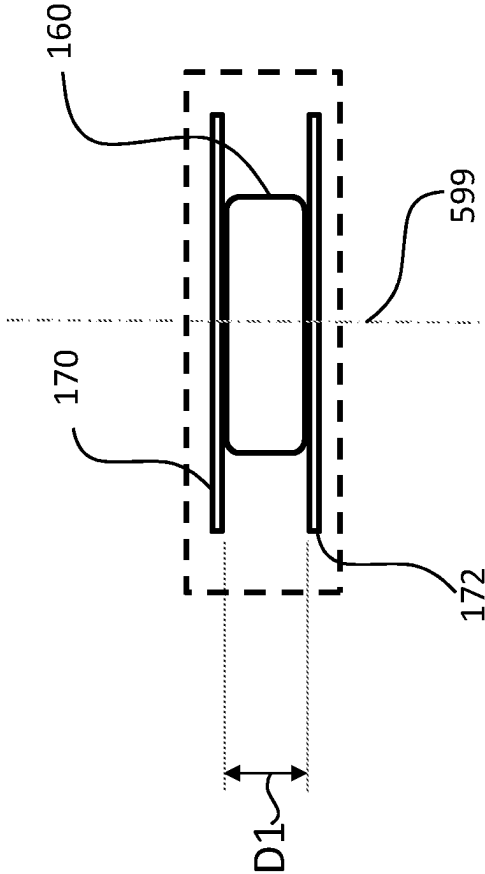


FIG. 7B

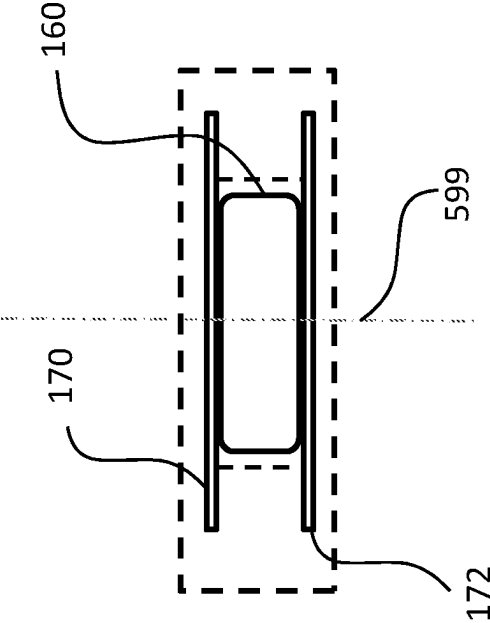


FIG. 7C

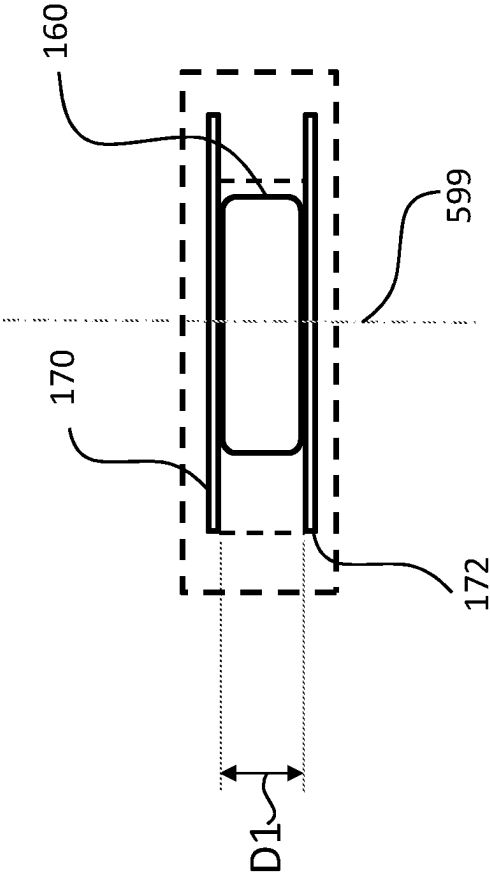




FIG. 7D

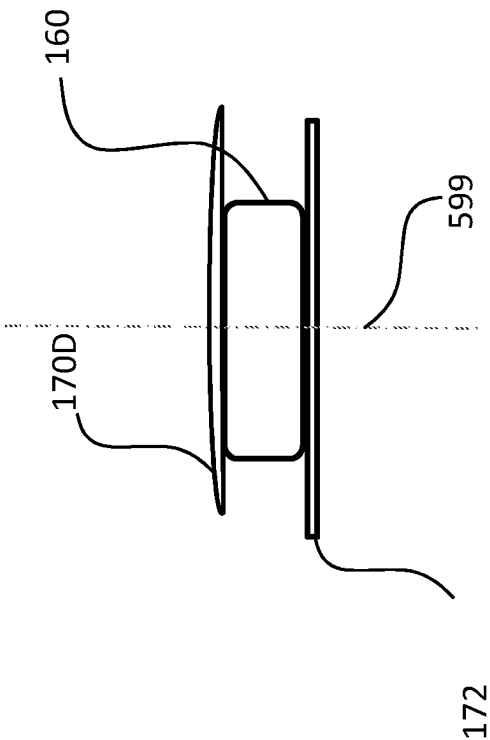


FIG. 8

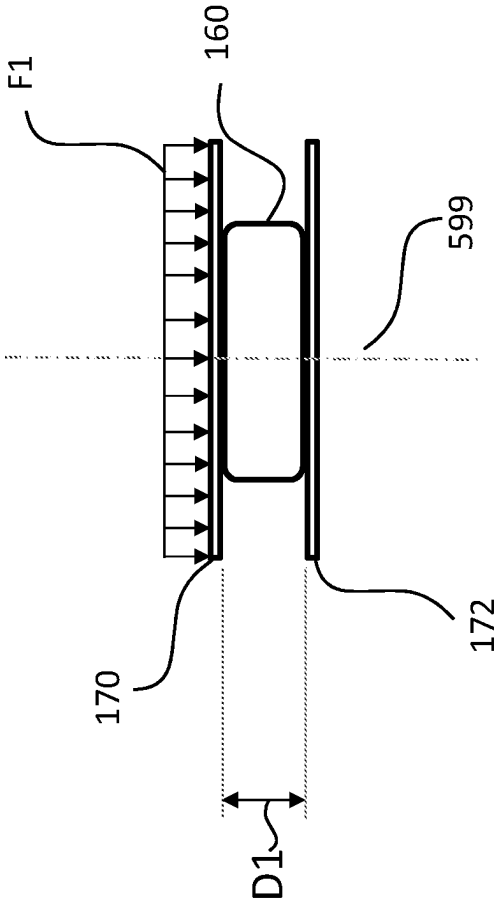


FIG. 9

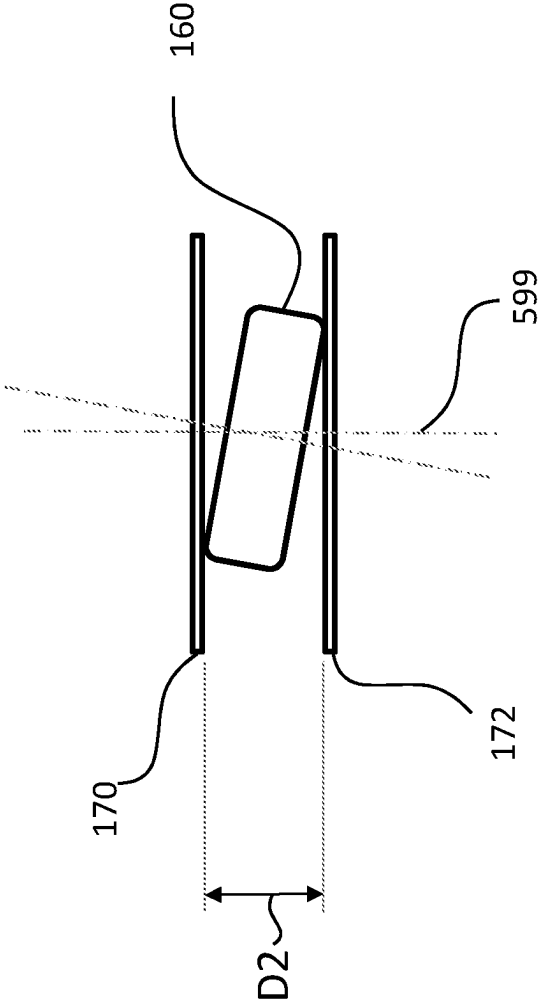


FIG. 10

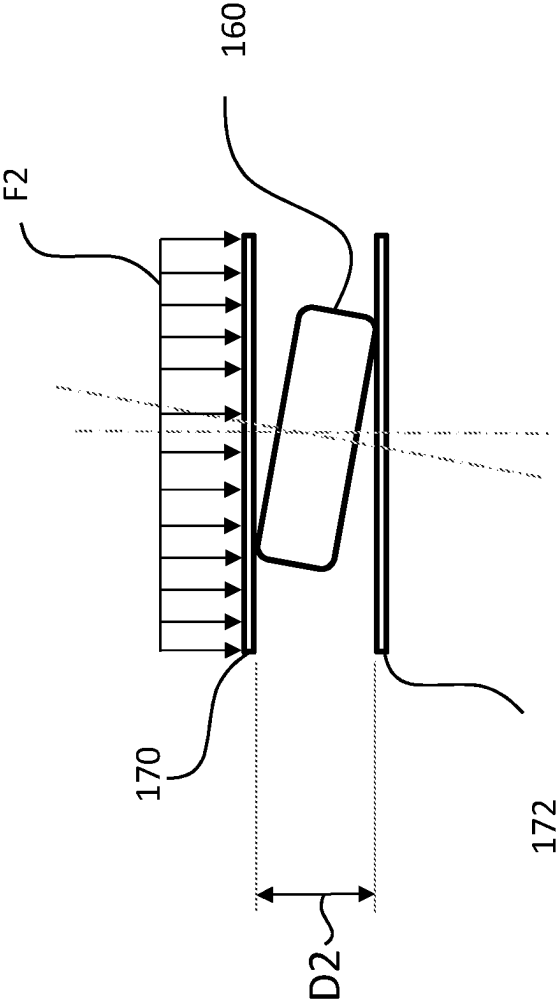


FIG. 11

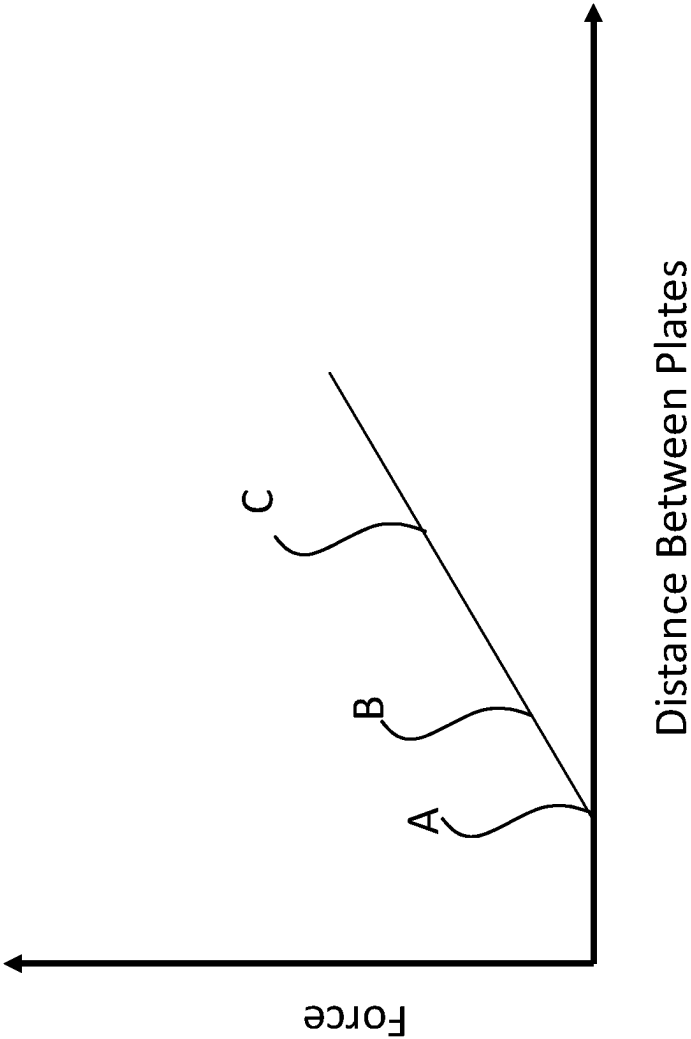


FIG. 12

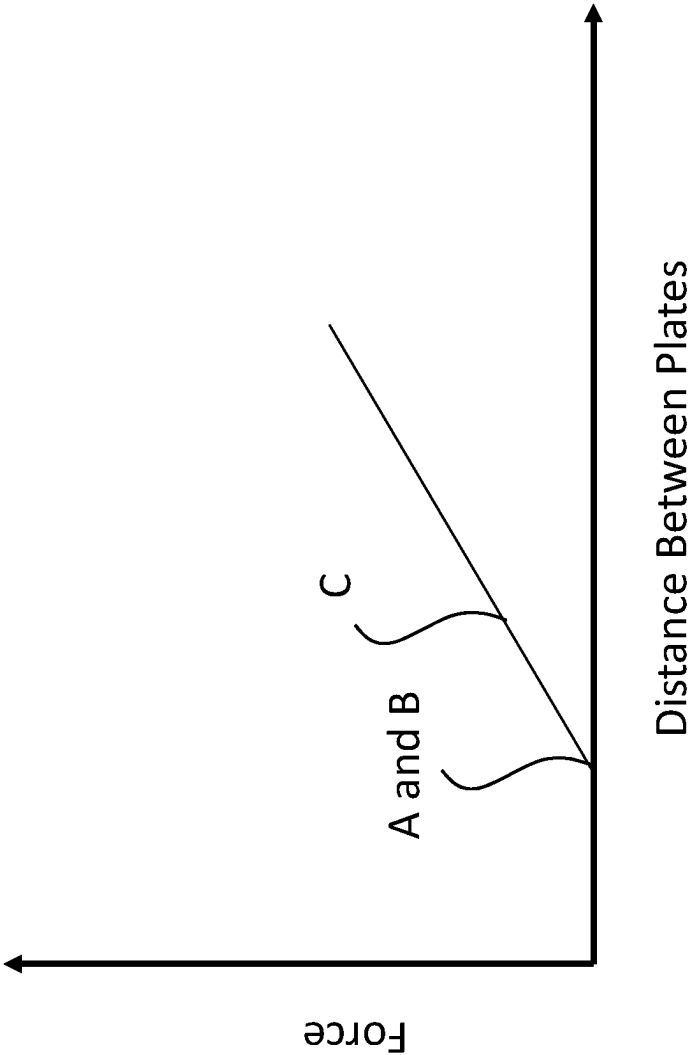


FIG. 13

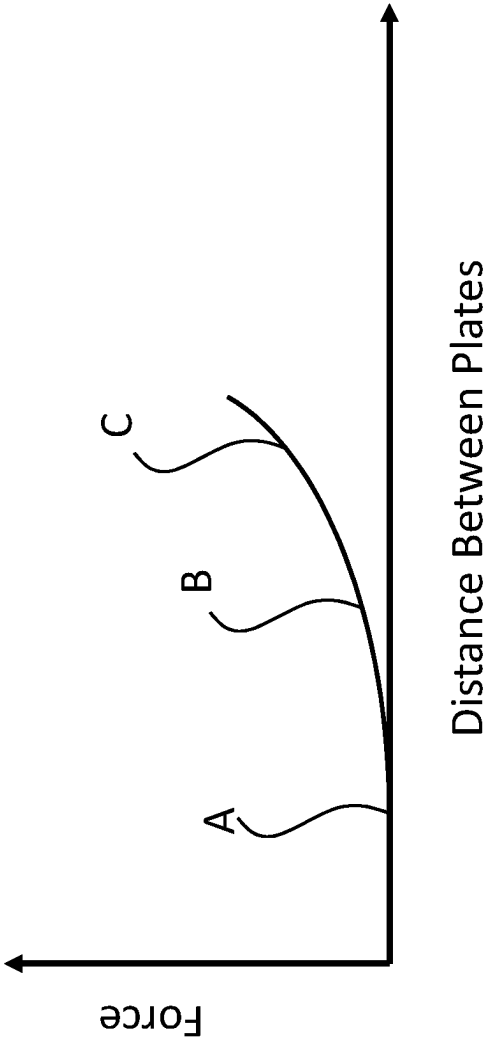


FIG. 14

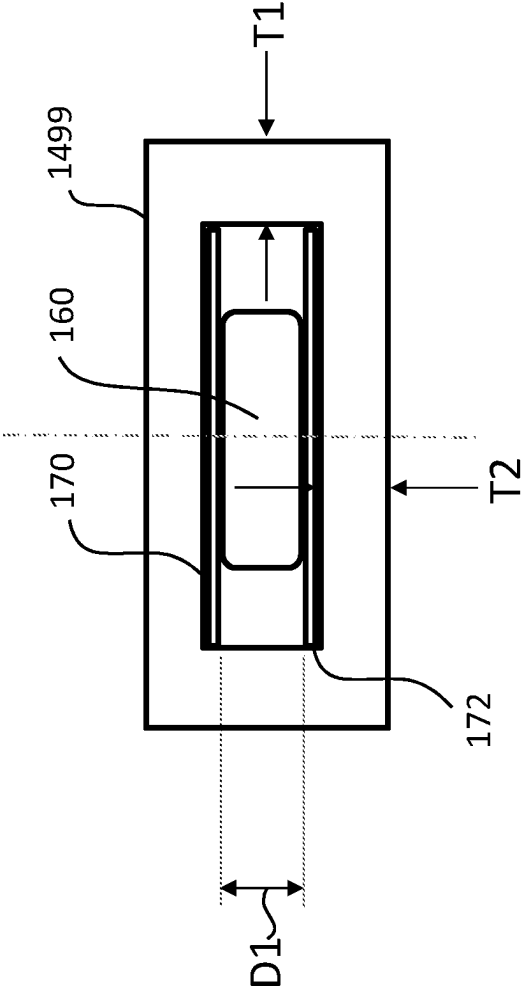




FIG. 15

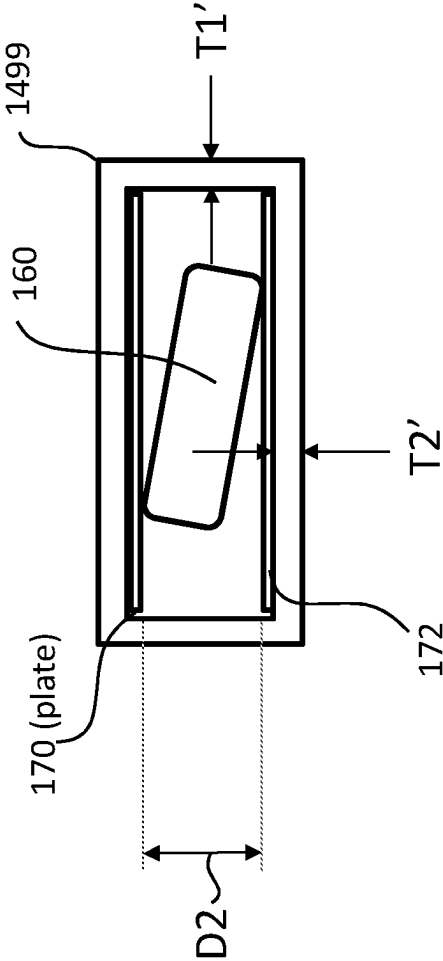


FIG. 16A

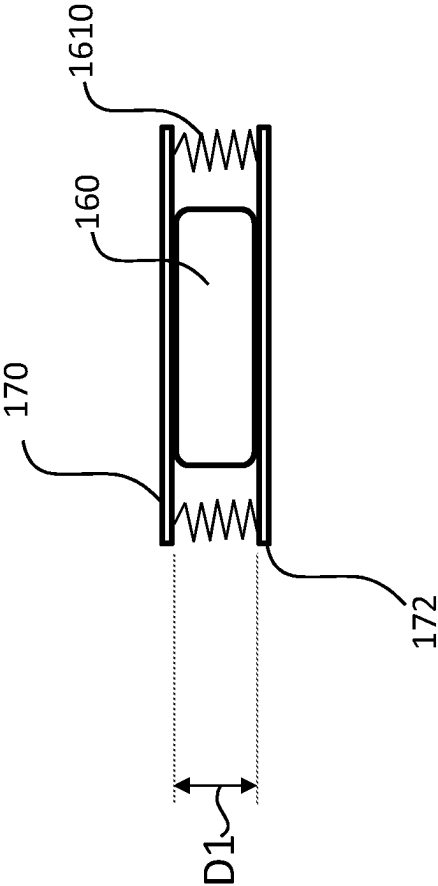


FIG. 16B

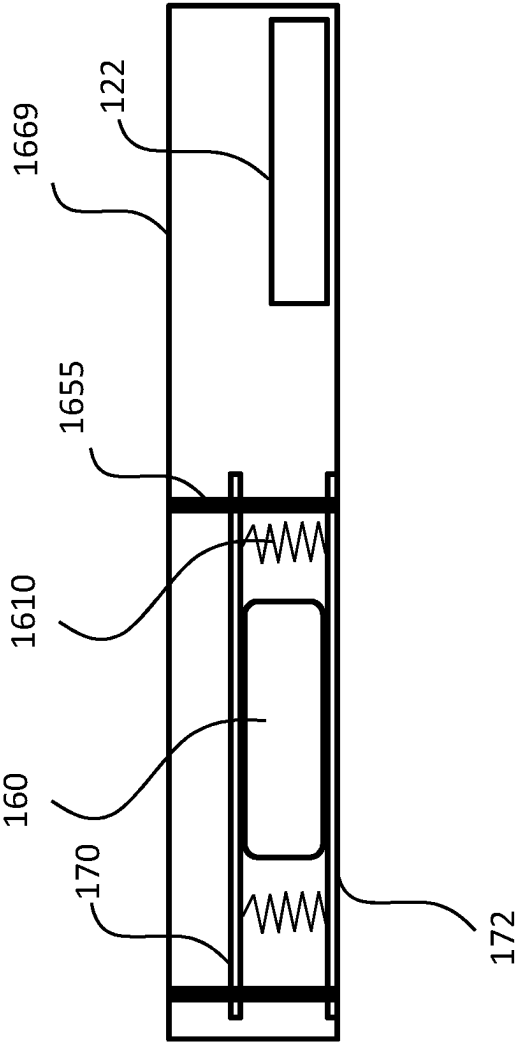


FIG. 16C

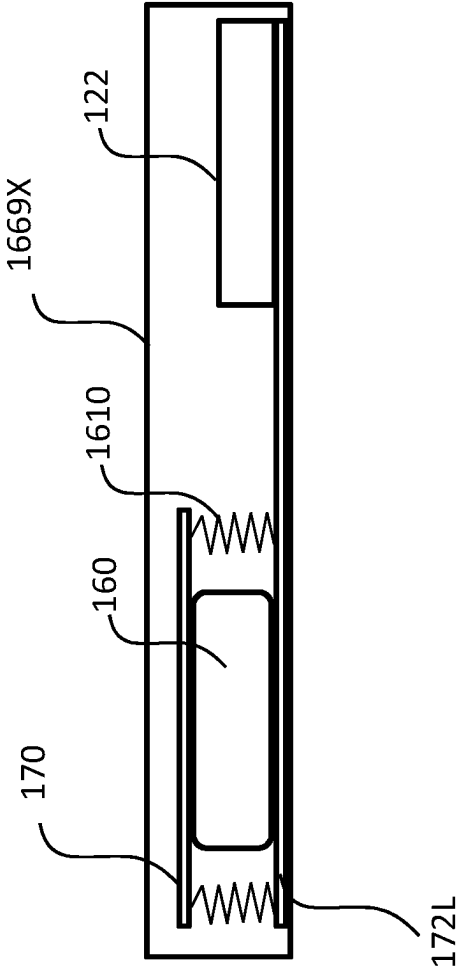


FIG. 16D

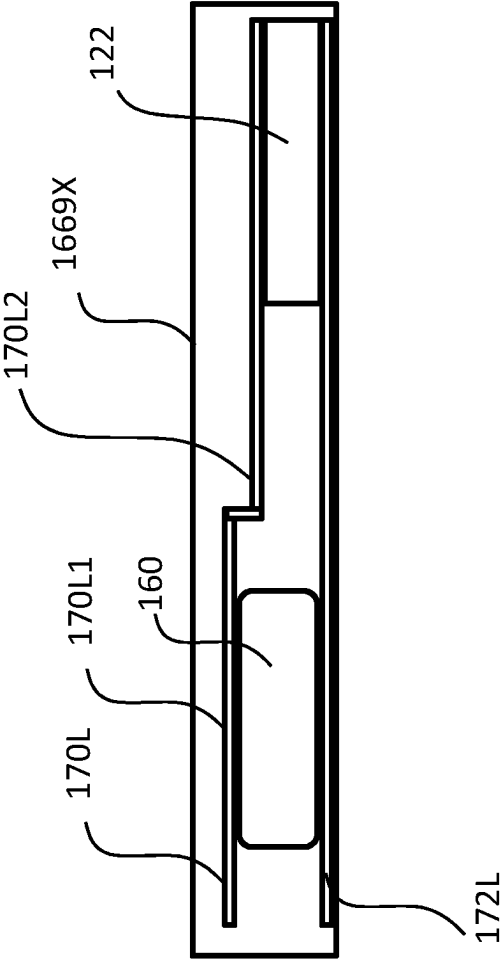


FIG. 17

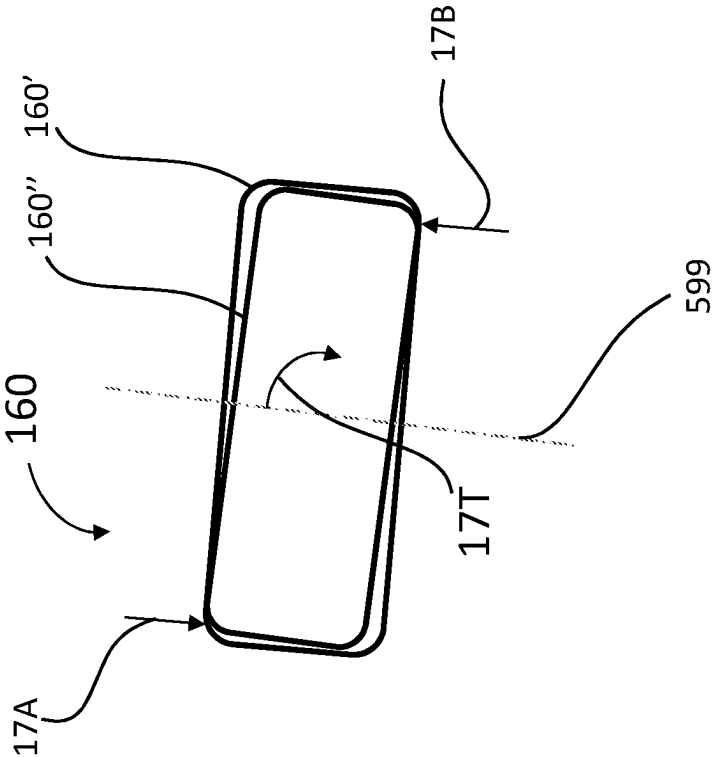


FIG. 18A

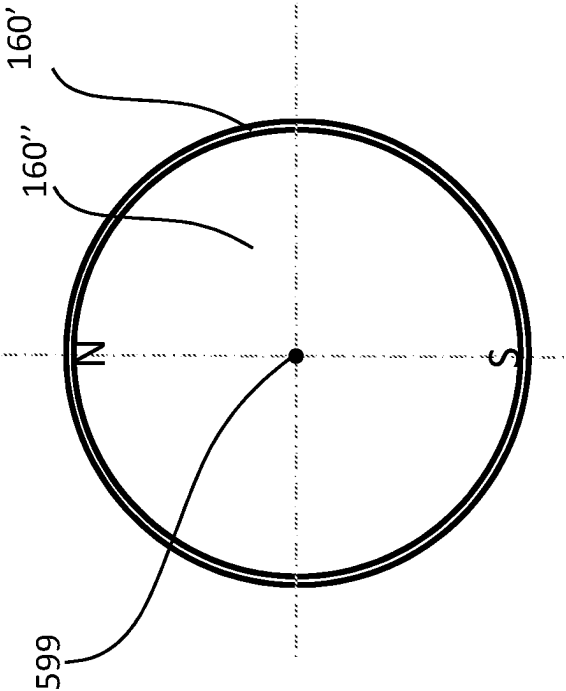


FIG. 18B

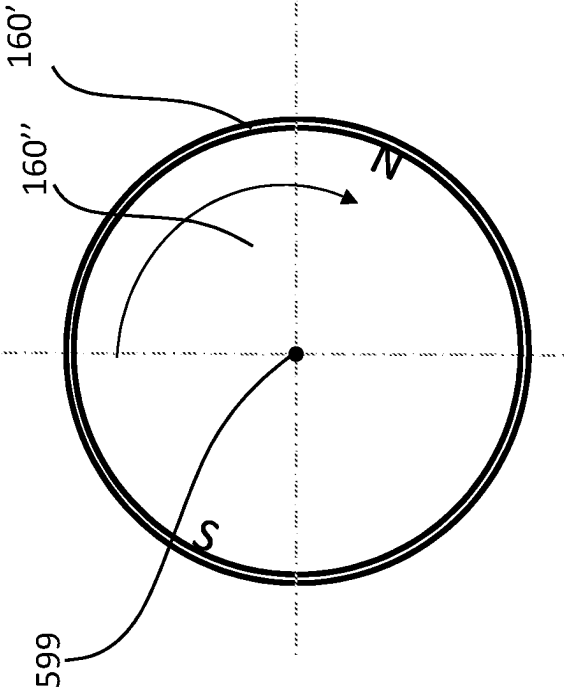




FIG. 18C

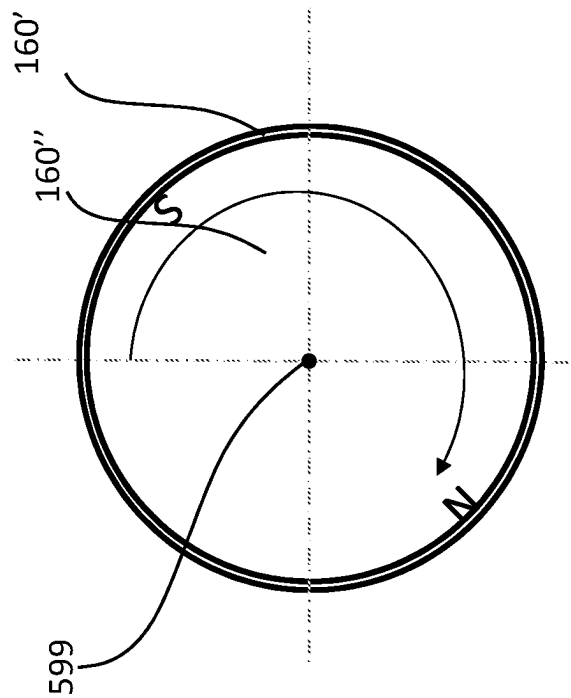
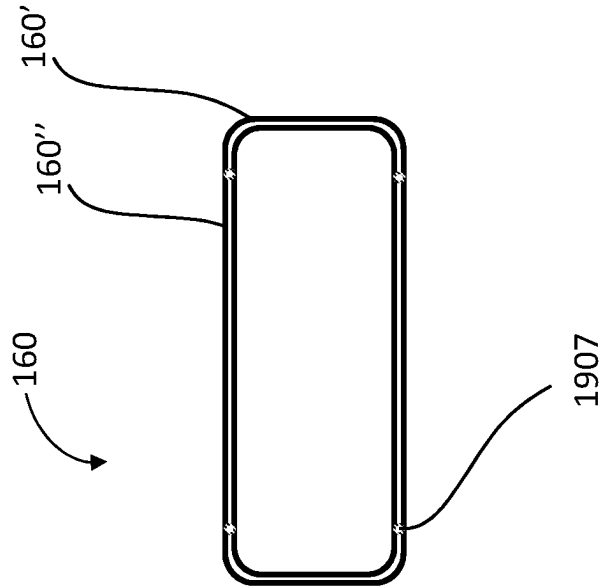


FIG. 19



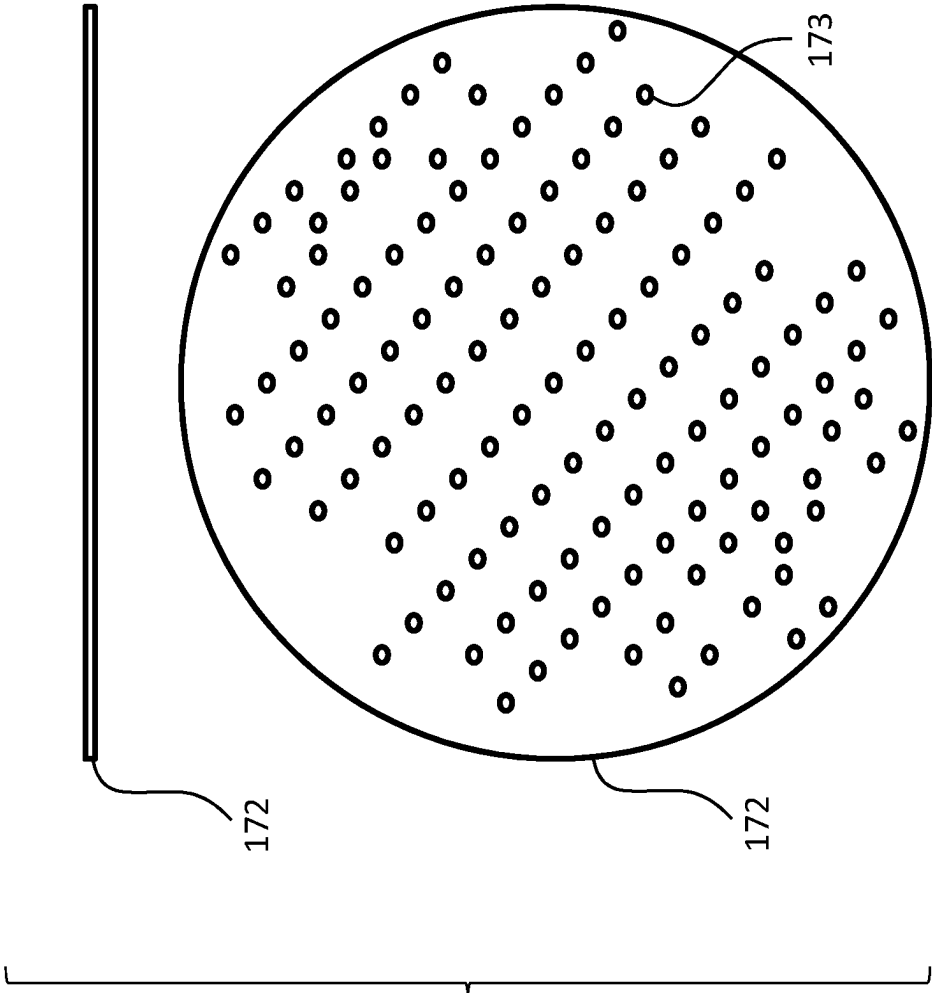


FIG. 20

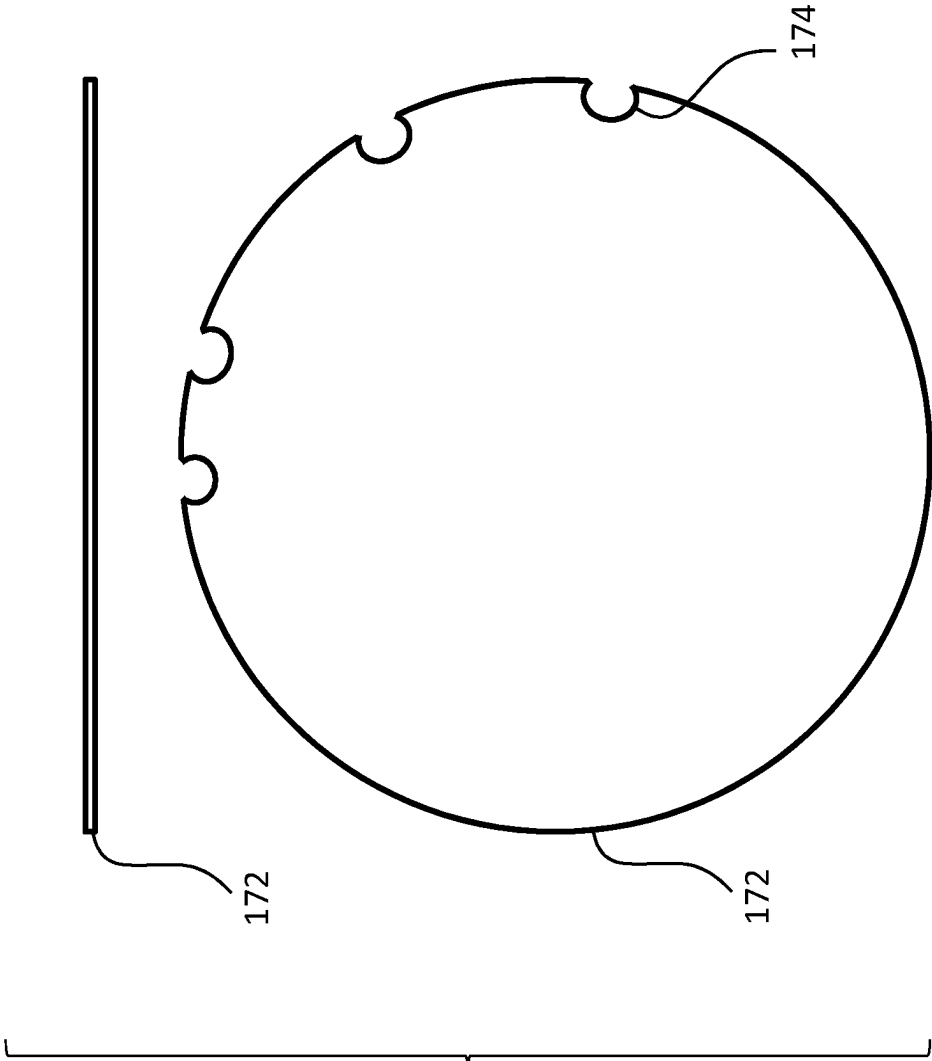


FIG. 21

FIG. 22

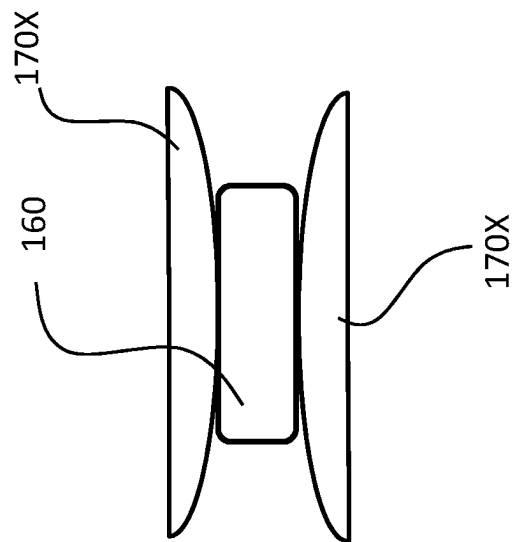


FIG. 23A

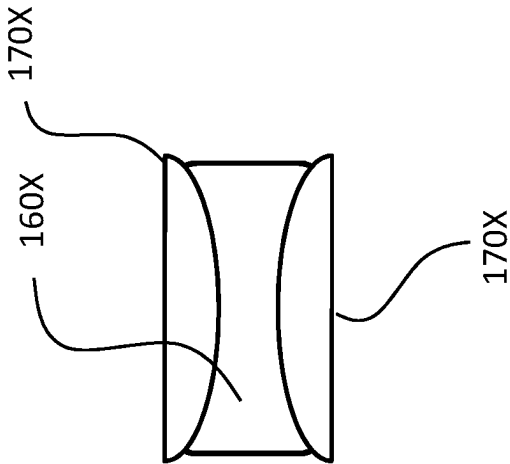


FIG. 23B

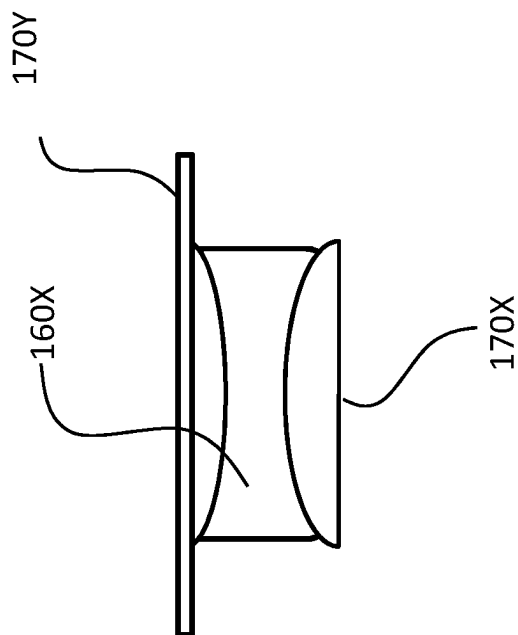


FIG. 23C

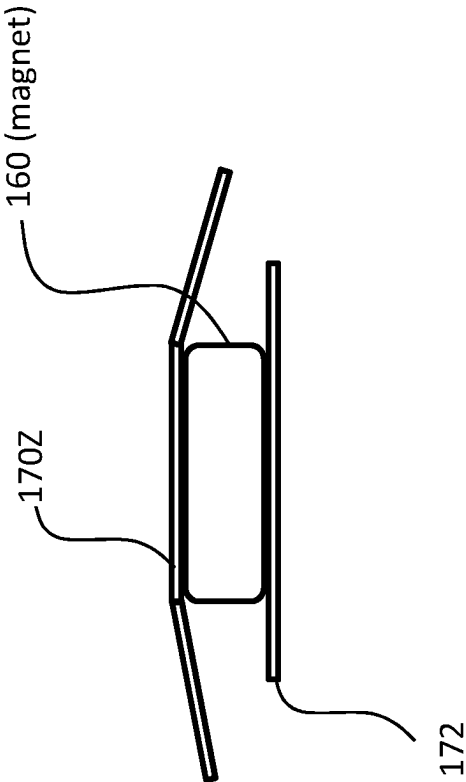




FIG. 23D

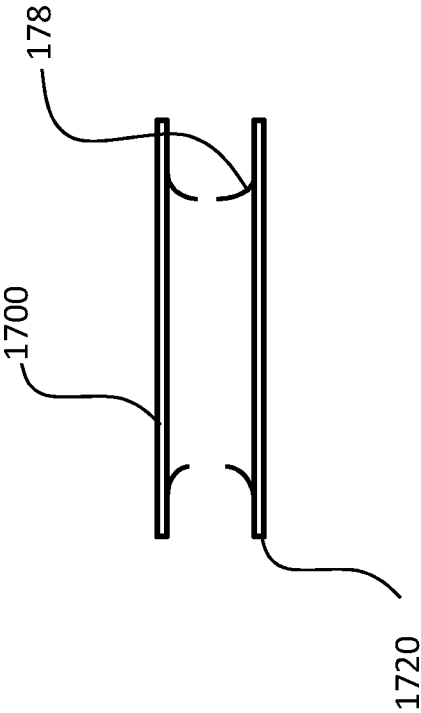


FIG. 23E

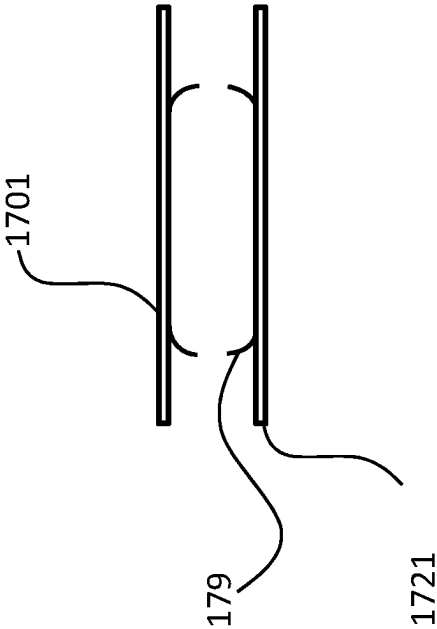


FIG. 24

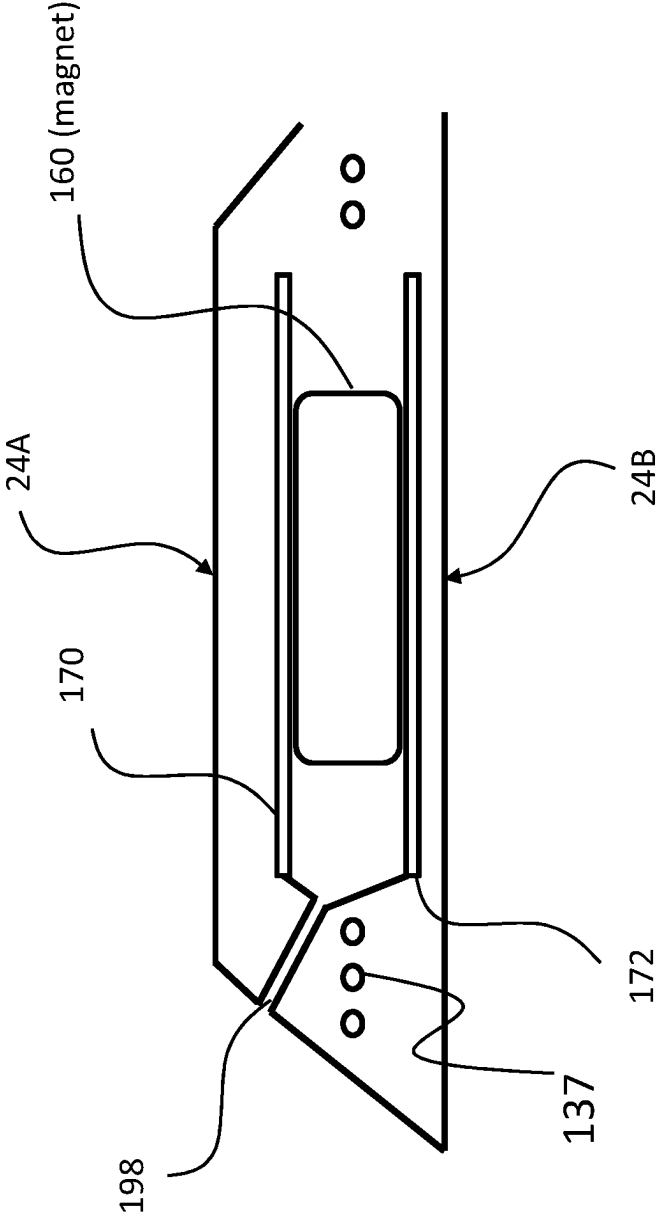


FIG. 25

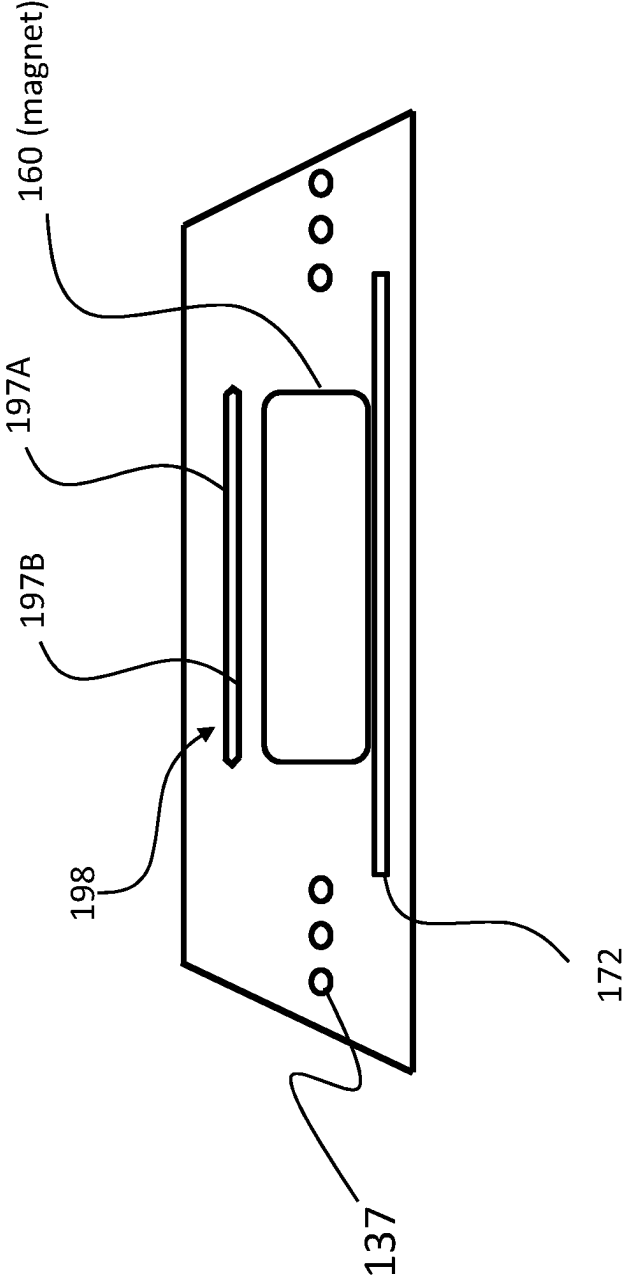


FIG. 26

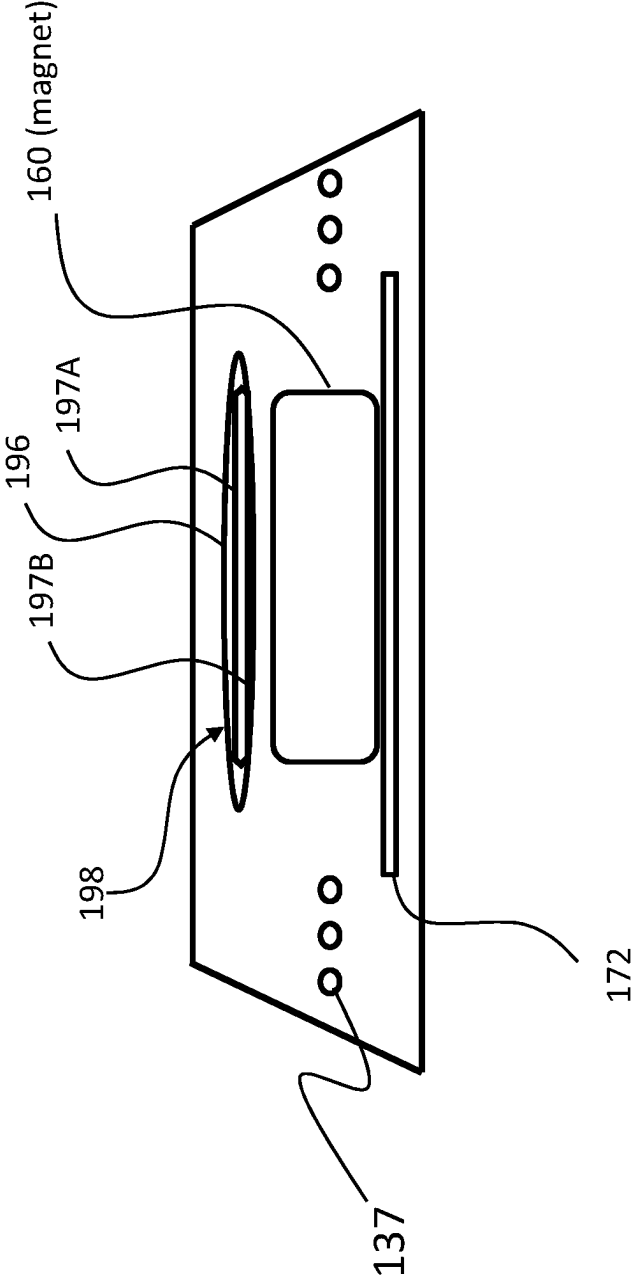


FIG. 27A



FIG. 27B

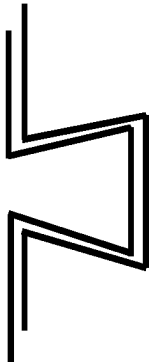


FIG. 27C

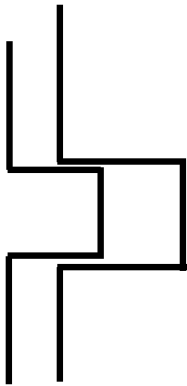


FIG. 28A

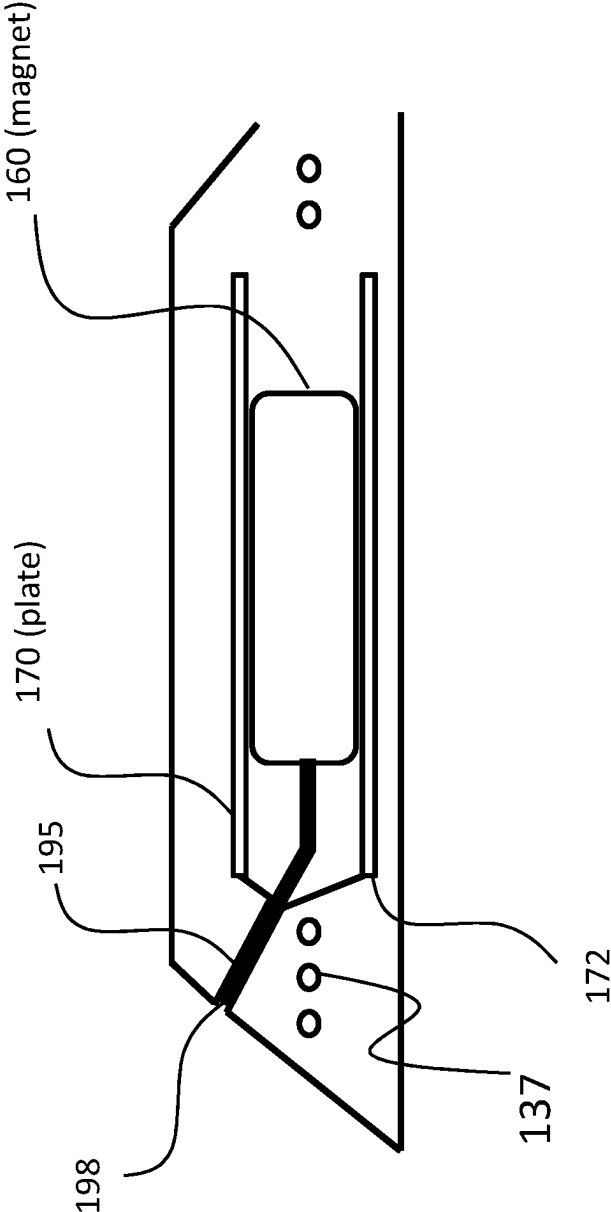


FIG. 28B

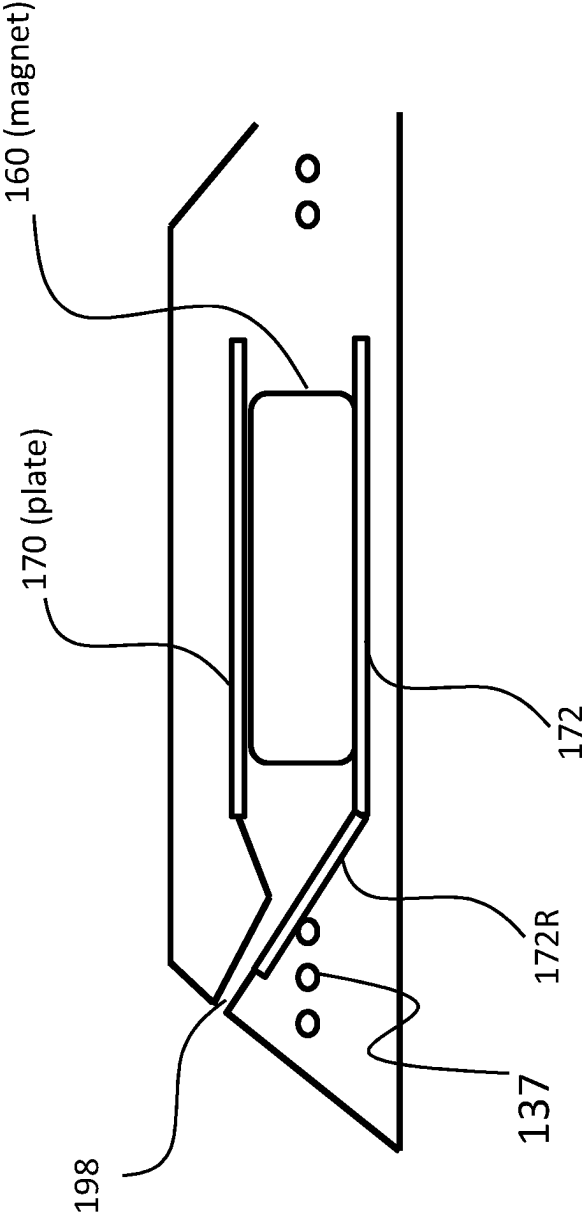




FIG. 28C

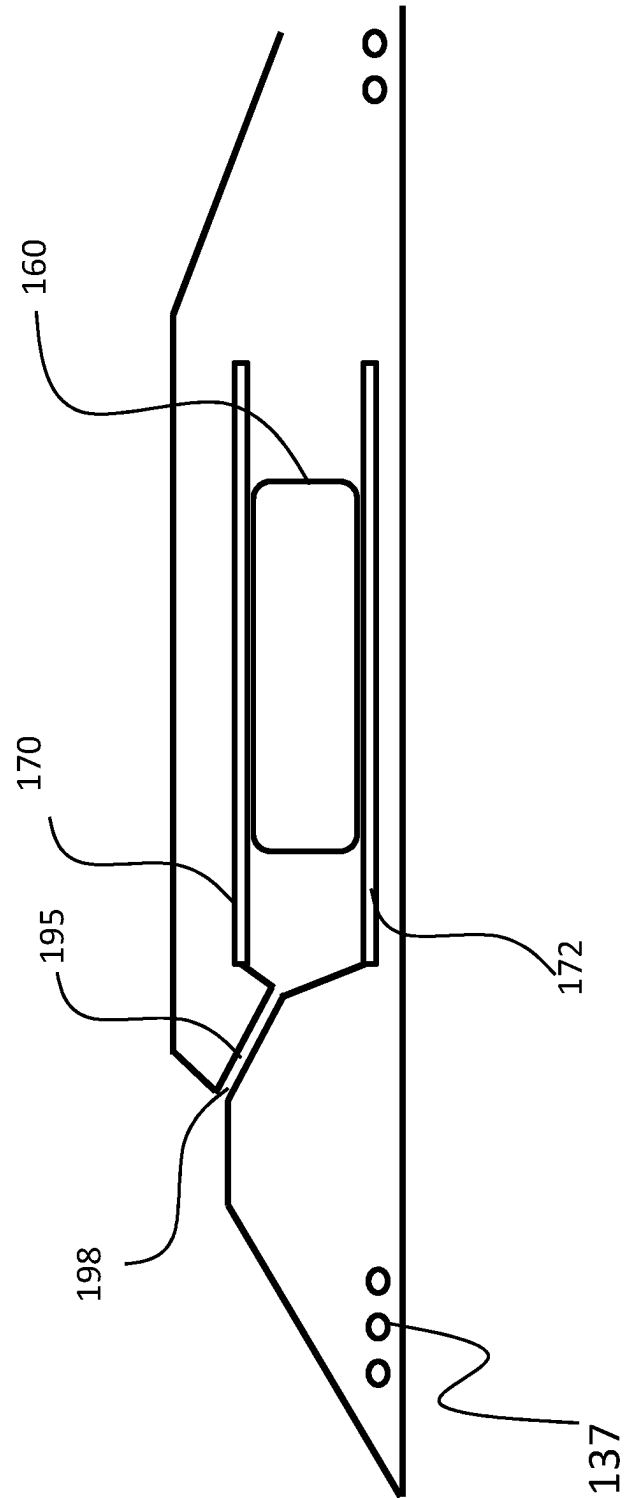


FIG. 29

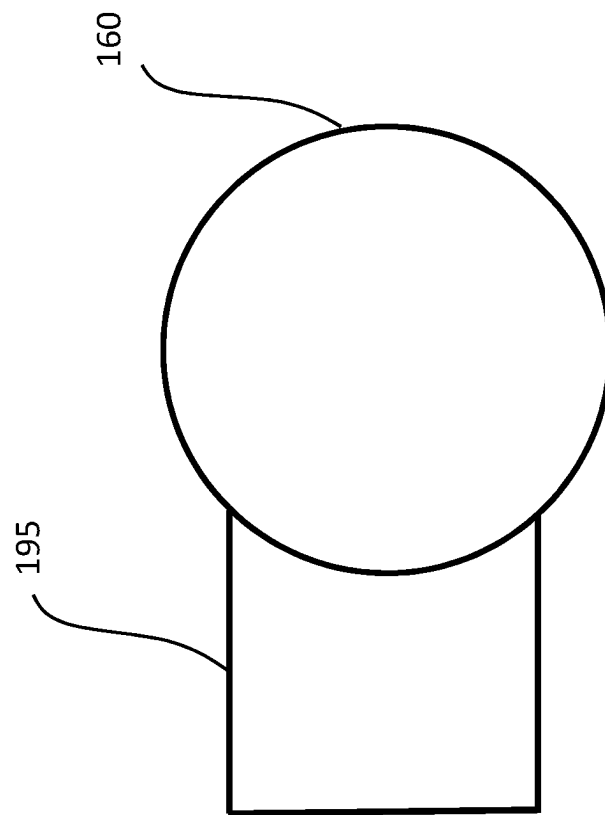


FIG. 30

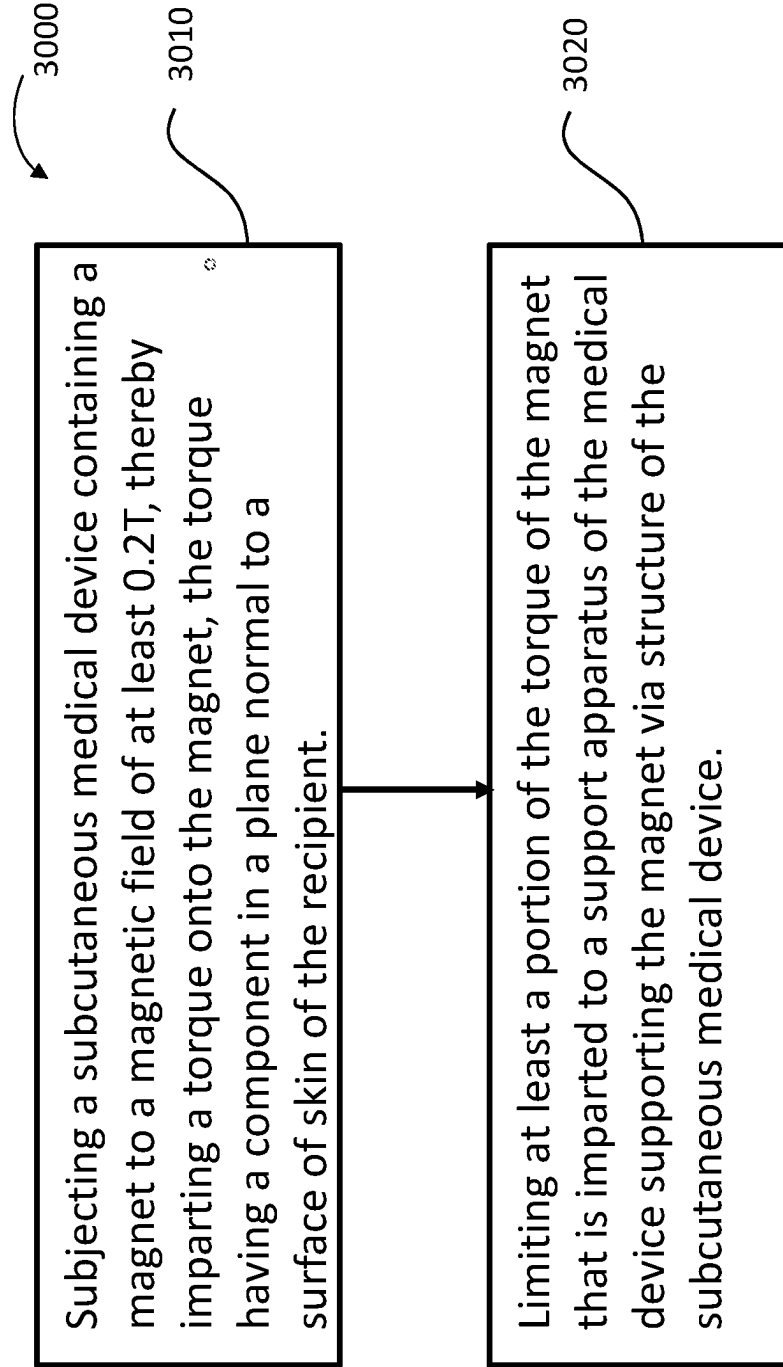


FIG. 31

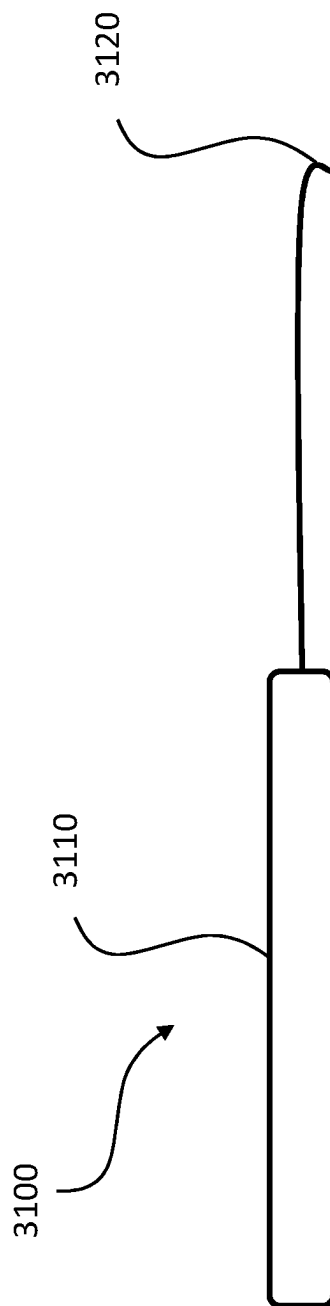


FIG. 32

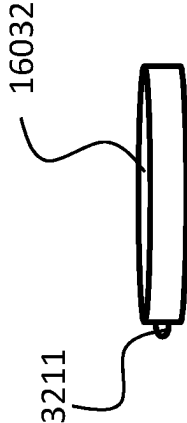


FIG. 34

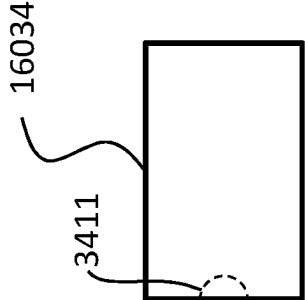


FIG. 33

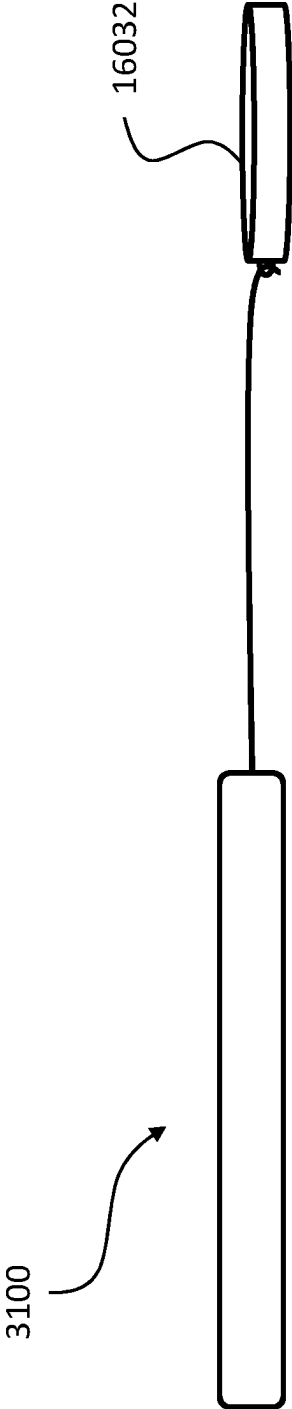
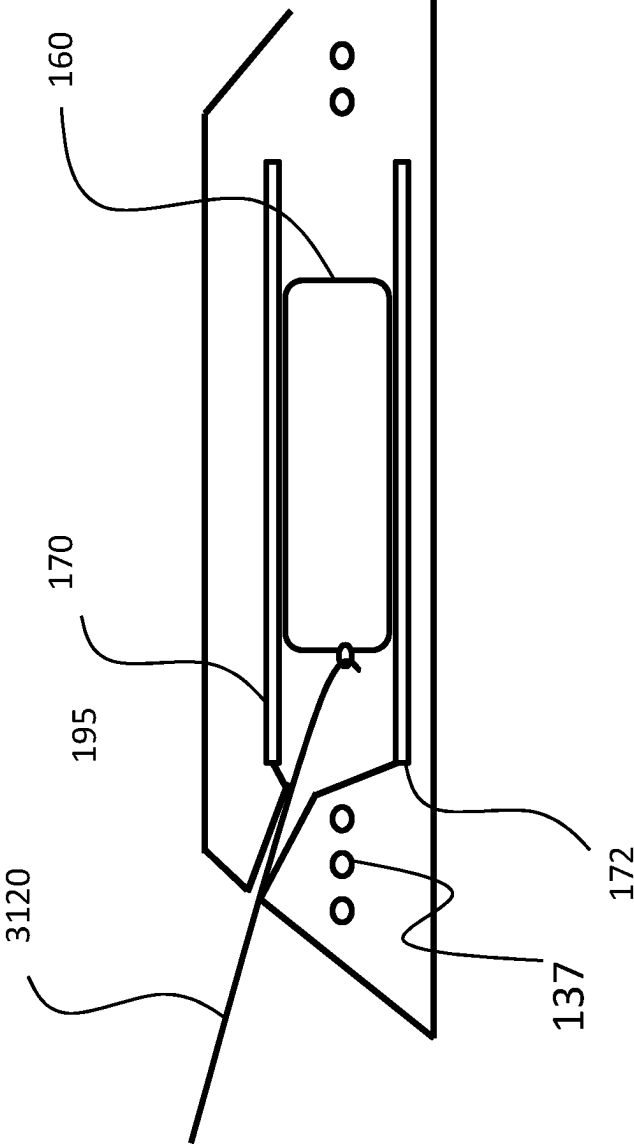


FIG. 35



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**MAGNET MANAGEMENT MRI  
COMPATIBILITY****CROSS-REFERENCE TO RELATED  
APPLICATIONS**

This application is a Continuation application of U.S. patent application Ser. No. 16/195,655, filed Nov. 19, 2018, which is a Continuation application of U.S. patent application Ser. No. 15/010,410, filed Jan. 29, 2016, now U.S. Pat. No. 10,130,807, which claims priority from Provisional U.S. Patent Application Ser. No. 62/174,788, entitled MAGNET MANAGEMENT MRI COMPATIBILITY, filed on Jun. 12, 2015, naming Charles Roger LEIGH of Australia as an inventor, the entire contents of that application being incorporated herein by reference in its entirety.

**BACKGROUND**

Hearing loss, which may be due to many different causes, is generally of two types: conductive and sensorineural. Sensorineural hearing loss is due to the absence or destruction of the hair cells in the cochlea that transduce sound signals into nerve impulses. Various hearing prostheses are commercially available to provide individuals suffering from sensorineural hearing loss with the ability to perceive sound. One example of a hearing prosthesis is a cochlear implant.

Conductive hearing loss occurs when the normal mechanical pathways that provide sound to hair cells in the cochlea are impeded, for example, by damage to the ossicular chain or the ear canal. Individuals suffering from conductive hearing loss may retain some form of residual hearing because the hair cells in the cochlea may remain undamaged.

Individuals suffering from hearing loss typically receive an acoustic hearing aid. Conventional hearing aids rely on principles of air conduction to transmit acoustic signals to the cochlea. In particular, a hearing aid typically uses an arrangement positioned in the recipient's ear canal or on the outer ear to amplify a sound received by the outer ear of the recipient. This amplified sound reaches the cochlea causing motion of the perilymph and stimulation of the auditory nerve. Cases of conductive hearing loss typically are treated by means of bone conduction hearing aids. In contrast to conventional hearing aids, these devices use a mechanical actuator that is coupled to the skull bone to apply the amplified sound.

In contrast to hearing aids, which rely primarily on the principles of air conduction, certain types of hearing prostheses, commonly referred to as cochlear implants, convert a received sound into electrical stimulation. The electrical stimulation is applied to the cochlea, which results in the perception of the received sound.

Many devices, such as medical devices that interface with a recipient, have structural and/or functional features where there is utilitarian value in adjusting such features for an individual recipient. The process by which a device that interfaces with or otherwise is used by the recipient is tailored or customized or otherwise adjusted for the specific needs or specific wants or specific characteristics of the recipient is commonly referred to as fitting. One type of medical device where there is utilitarian value in fitting such to an individual recipient is the above-noted cochlear implant. That said, other types of medical devices, such as

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other types of hearing prostheses, exist where there is utilitarian value in fitting such to the recipient.

**SUMMARY**

In accordance with an exemplary embodiment, there is an implantable medical device, comprising a magnet, and a body encompassing the magnet, wherein the implantable medical device includes structural components in the body configured to move away from one another upon initial rotation of the magnet relative to the body when the magnet is subjected to an externally generated magnetic field that imparts a torque onto the magnet, thereby limiting rotation of the magnet beyond the initial rotation.

In accordance with another exemplary embodiment, there is an implantable medical device, comprising a magnet apparatus, and a body encompassing the magnet apparatus, wherein the implantable medical device resists rotation of the magnet apparatus relative to the body in at least one plane when subjected to an externally generated magnetic field that imparts a torque onto the magnet apparatus due to a component relative to which the magnet apparatus is slidable, wherein the component located within the body.

In accordance with another exemplary embodiment, there is an implantable medical device, comprising a magnet and an elastomeric body encompassing the magnet, wherein the body has a slit configured to enable passage of the magnet therethrough.

In accordance with another exemplary embodiment, there is a method, comprising subjecting a subcutaneous medical device containing a magnet to a magnetic field of at least 0.2 T, thereby imparting a torque onto the magnet, the torque having a component in a plane normal to a surface of skin of the recipient, and limiting at least a portion of the torque of the magnet that is imparted to a support apparatus of the medical device supporting the magnet via structure of the subcutaneous medical device.

**BRIEF DESCRIPTION OF THE DRAWINGS**

Embodiments are described below with reference to the attached drawings, in which:

FIG. 1A is a perspective view of an exemplary hearing prosthesis in which at least some of the teachings detailed herein are applicable;

FIG. 1B is a top view of an exemplary hearing prosthesis in which at least some of the teachings detailed herein are applicable;

FIG. 1C is a side view of an exemplary hearing prosthesis in which at least some of the teachings detailed herein are applicable;

FIG. 2A is a functional block diagram of a prosthesis, in accordance with embodiments of the present invention;

FIG. 2B is an alternate functional block diagram of a prosthesis, in accordance with embodiments of the present invention;

FIG. 3A is a functional block diagram of a cochlear implant, in accordance with embodiments of the present invention;

FIG. 3B is an alternate functional block diagram of a cochlear implant, in accordance with embodiments of the present invention;

FIG. 3C is yet another alternate functional block diagram of a cochlear plant, accordance with embodiments of the present invention;

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FIG. 4A is a simplified schematic diagram of a transceiver unit of an external device in accordance with embodiments of the present invention;

FIG. 4B is a simplified schematic diagram of a transmitter unit of an external device in accordance with embodiments of the present invention;

FIG. 4C is a simplified schematic diagram of a stimulator/receiver unit including a data receiver of an implantable device in accordance with embodiments of the present invention;

FIG. 4D is a simplified schematic diagram of a stimulator/receiver unit including a data transceiver of an implantable device in accordance with embodiments of the present invention;

FIG. 4E is a simplified schematic diagram of a stimulator/receiver unit including a data receiver and a communication component configured to vary the effective coil area of an implantable device in accordance with embodiments of the present invention;

FIG. 4F is a simplified schematic diagram of a stimulator/receiver unit including a data transceiver and a communication component configured to vary the effective coil area of an implantable device in accordance with embodiments of the present invention;

FIG. 5 is an exemplary conceptual schematic of a magnet system arrangement according to an exemplary embodiment;

FIG. 6 is another exemplary conceptual schematic of a magnet system arrangement according to an exemplary embodiment;

FIGS. 7A-7D represent exemplary conceptual schematics of an assembly according to an exemplary embodiment;

FIG. 8 depicts a functional schematic of an exemplary scenario resulting from use of an exemplary embodiment;

FIG. 9 depicts another functional schematic of an exemplary scenario resulting from use of an exemplary embodiment;

FIG. 10 depicts another functional schematic of an exemplary scenario resulting from use of an exemplary embodiment;

FIGS. 11-13 depict exemplary conceptual data charts according to an exemplary embodiment relating force to distance between plates;

FIG. 14 represents an exemplary conceptual schematic of an assembly according to an exemplary embodiment;

FIG. 15 represents an exemplary scenario of conceptual use according to an exemplary embodiment;

FIGS. 16A-D present exemplary conceptual schematics of various assemblies according to various exemplary embodiments;

FIG. 17 represents an exemplary scenario of conceptual use according to an exemplary embodiment;

FIG. 18A represents an exemplary conceptual schematic of an assembly according to an exemplary embodiment;

FIG. 18B and FIG. 18C, represent an exemplary scenarios of conceptual use according to an exemplary embodiment;

FIG. 19 represents an exemplary conceptual schematic of an assembly according to an exemplary embodiment;

FIGS. 20-23E variously represent various exemplary conceptual schematics of various exemplary assemblies according to various exemplary embodiments;

FIGS. 24-28C variously represent various exemplary conceptual schematics of various exemplary assemblies according to various exemplary embodiments;

FIG. 29 represents an exemplary embodiment of a magnet apparatus according to an exemplary embodiment;

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FIG. 30 represents an exemplary flowchart according to an exemplary method of an exemplary embodiment;

FIG. 31 represents an exemplary tool according to an exemplary embodiment utilized in some exemplary methods according to the teachings detailed herein;

FIG. 32 represents an exemplary magnet apparatus according to an exemplary embodiment;

FIG. 33 depicts use of the tool of FIG. 31 with the exemplary magnet apparatus of FIG. 32 according to an exemplary embodiment;

FIG. 34 represents an exemplary magnet apparatus according to an exemplary embodiment; and

FIG. 35 represents an exemplary use of the tool of FIG. 31 with the embodiment of FIG. 25.

## DETAILED DESCRIPTION

Exemplary embodiments will be described in terms of a cochlear implant. That said, it is noted that the teachings detailed herein and/or variations thereof can be utilized with other types of hearing prosthesis, such as by way of example, bone conduction devices, DACI/DACS/middle ear implants, etc. Still further, it is noted that the teachings detailed herein and/or variations thereof can be utilized with other types of prostheses, such as pacemakers, muscle stimulators, etc. In some instances, the teachings detailed herein and/or variations thereof are applicable to any type of implanted component (herein referred to as a medical device) having a magnet that is implantable in a recipient.

FIG. 1A is a perspective view of a cochlear implant, referred to as cochlear implant 100, implanted in a recipient, to which some embodiments detailed herein and/or variations thereof are applicable. The cochlear implant 100 is part of a system 10 that can include external components in some embodiments, as will be detailed below. It is noted that the teachings detailed herein are applicable, in at least some embodiments, to partially implantable and/or totally implantable cochlear implants (i.e., with regard to the latter, such as those having an implanted microphone). It is further noted that the teachings detailed herein are also applicable to other stimulating devices that utilize an electrical current beyond cochlear implants (e.g., auditory brain stimulators, pacemakers, etc.). Additionally, it is noted that the teachings detailed herein are also applicable to other types of hearing prosthesis, such as by way of example only and not by way of limitation, bone conduction devices, direct acoustic cochlear stimulators, middle ear implants, etc. Indeed, it is noted that the teachings detailed herein are also applicable to so-called hybrid devices. In an exemplary embodiment, these hybrid devices apply both electrical stimulation and acoustic stimulation to the recipient. Any type of hearing prosthesis to which the teachings detailed herein and/or variations thereof that can have utility can be used in some embodiments of the teachings detailed herein.

In view of the above, it is to be understood that at least some embodiments detailed herein and/or variations thereof are directed towards a body-worn sensory supplement medical device (e.g., the hearing prosthesis of FIG. 1A, which supplements the hearing sense, even in instances where all natural hearing capabilities have been lost). It is noted that at least some exemplary embodiments of some sensory supplement medical devices are directed towards devices such as conventional hearing aids, which supplement the hearing sense in instances where some natural hearing capabilities have been retained, and visual prostheses (both those that are applicable to recipients having some natural vision capabilities remaining and to recipients having no



natural vision capabilities remaining). Accordingly, the teachings detailed herein are applicable to any type of sensory supplement medical device to which the teachings detailed herein are enabled for use therein in a utilitarian manner. In this regard, the phrase sensory supplement medical device refers to any device that functions to provide sensation to a recipient irrespective of whether the applicable natural sense is only partially impaired or completely impaired.

The recipient has an outer ear **101**, a middle ear **105** and an inner ear **107**. Components of outer ear **101**, middle ear **105** and inner ear **107** are described below, followed by a description of cochlear implant **100**.

In a fully functional ear, outer ear **101** comprises an auricle **110** and an ear canal **102**. An acoustic pressure or sound wave **103** is collected by auricle **110** and channeled into and through ear canal **102**. Disposed across the distal end of ear channel **102** is a tympanic membrane **104** which vibrates in response to sound wave **103**. This vibration is coupled to oval window or fenestra ovalis **112** through three bones of middle ear **105**, collectively referred to as the ossicles **106** and comprising the malleus **108**, the incus **109** and the stapes **111**. Bones **108**, **109** and **111** of middle ear **105** serve to filter and amplify sound wave **103**, causing oval window **112** to articulate, or vibrate in response to vibration of tympanic membrane **104**. This vibration sets up waves of fluid motion of the perilymph within cochlea **140**. Such fluid motion, in turn, activates tiny hair cells (not shown) inside of cochlea **140**. Activation of the hair cells causes appropriate nerve impulses to be generated and transferred through the spiral ganglion cells (not shown) and auditory nerve **114** to the brain (also not shown) where they are perceived as sound.

As shown, cochlear implant **100** comprises one or more components which are temporarily or permanently implanted in the recipient. Cochlear implant **100** is shown in FIG. 1A with an external device **142**, that is part of system **10** (along with cochlear implant **100**), which, as described below, is configured to provide power to the cochlear implant, and where the implanted cochlear implant includes a battery, that is recharged by the power provided from the external device **142**.

In the illustrative arrangement of FIG. 1A, external device **142** can comprise a power source (not shown) disposed in a Behind-The-Ear (BTE) unit **126**. External device **142** also includes components of a transcutaneous energy transfer link, referred to as an external energy transfer assembly. The transcutaneous energy transfer link is used to transfer power and/or data to cochlear implant **100**. Various types of energy transfer, such as infrared (IR), electromagnetic, capacitive and inductive transfer, may be used to transfer the power and/or data from external device **142** to cochlear implant **100**. In the illustrative embodiments of FIG. 1A, the external energy transfer assembly comprises an external coil **130** that forms part of an inductive radio frequency (RF) communication link. External coil **130** is typically a wire antenna coil comprised of multiple turns of electrically insulated single-strand or multi-strand platinum or gold wire. External device **142** also includes a magnet (not shown) positioned within the turns of wire of external coil **130**. It should be appreciated that the external device shown in FIG. 1A is merely illustrative, and other external devices may be used with embodiments of the present invention.

Cochlear implant **100** comprises an internal energy transfer assembly **132** which can be positioned in a recess of the temporal bone adjacent auricle **110** of the recipient. As detailed below, internal energy transfer assembly **132** is a

component of the transcutaneous energy transfer link and receives power and/or data from external device **142**. In the illustrative embodiment, the energy transfer link comprises an inductive RF link, and internal energy transfer assembly **132** comprises a primary internal coil assembly **136**. Internal coil assembly **136** typically includes a wire antenna coil comprised of multiple turns of electrically insulated single-strand or multi-strand platinum or gold wire, as will be described in greater detail below.

Cochlear implant **100** further comprises a main implantable component **120** and an elongate electrode assembly **118**. Collectively, the coil assembly **136**, the main implantable component **120**, and the electrode assembly **118** correspond to the implantable component of the system **10**.

In some embodiments, internal energy transfer assembly **132** and main implantable component **120** are hermetically sealed within a biocompatible housing. In some embodiments, main implantable component **120** includes an implantable microphone assembly (not shown) and a sound processing unit (not shown) to convert the sound signals received by the implantable microphone or via internal energy transfer assembly **132** to data signals. That said, in some alternative embodiments, the implantable microphone assembly can be located in a separate implantable component (e.g., that has its own housing assembly, etc.) that is in signal communication with the main implantable component **120** (e.g., via leads or the like between the separate implantable component and the main implantable component **120**). In at least some embodiments, the teachings detailed herein and/or variations thereof can be utilized with any type of implantable microphone arrangement.

Main implantable component **120** further includes a stimulator unit (also not shown in FIG. 1A) which generates electrical stimulation signals based on the data signals. The electrical stimulation signals are delivered to the recipient via elongate electrode assembly **118**.

Elongate electrode assembly **118** has a proximal end connected to main implantable component **120**, and a distal end implanted in cochlea **140**. Electrode assembly **118** extends from main implantable component **120** to cochlea **140** through mastoid bone **119**. In some embodiments electrode assembly **118** may be implanted at least in basal region **116**, and sometimes further. For example, electrode assembly **118** may extend towards apical end of cochlea **140**, referred to as cochlea apex **134**. In certain circumstances, electrode assembly **118** may be inserted into cochlea **140** via a cochleostomy **122**. In other circumstances, a cochleostomy may be formed through round window **121**, oval window **112**, the promontory **123** or through an apical turn **147** of cochlea **140**.

Electrode assembly **118** comprises a longitudinally aligned and distally extending array **146** of electrodes **148**, disposed along a length thereof. As noted, a stimulator unit generates stimulation signals which are applied by electrodes **148** to cochlea **140**, thereby stimulating auditory nerve **114**.

FIG. 1B depicts an exemplary high-level diagram of the implantable component **100** of the system **10**, looking downward from outside the skull towards the skull. As can be seen, implantable component **100** includes a magnet **160** that is surrounded by a coil **137** that is in two-way communication (although in other embodiments, the communication is one-way) with a stimulator unit **122**, which in turn is in communication with the electrode assembly **118**. Implantable component **100** further includes a plate **170** that is located above the magnet **160** (relative to the view of FIG. 1B). In the exemplary embodiment presented in FIG. 1B, the

longitudinal axis of the plate **170** is at least generally aligned (including aligned) with the magnet apparatus **160**, although in other embodiments, such alignment is not present. Not seen in FIG. 1B, but as can be seen in FIG. 1C (representing a side cross-sectional view of the implantable component **100** of FIG. 1B taken down the center of the implantable component **100**), is another plate **172** located on the opposite side of the magnet apparatus **160**, resulting in, in this exemplary embodiment, the magnet apparatus **160** being sandwiched by the plates. In at least some embodiments, plate **172** is identical to the plate **170**, while in other embodiments, the plates are different. Additional features of these plates will be described in greater detail below.

Still with reference to FIG. 1B, it is noted that the plate **170** (and the bottom plate), the stimulator unit **122**, and the magnet apparatus **170** are located in a housing made of an elastomeric material **199**, such as by way of example only and not by way of limitation, silicone. Hereinafter, the elastomeric material **199** of the housing will be often referred to as silicone. However, it is noted that any reference to silicone herein also corresponds to a reference to any other type of component that will enable the teachings detailed herein and/or variations thereof, such as, by way of example and not by way of limitation only, bio-compatible rubber, etc.

As can be seen in FIG. 1B, the housing made of elastomeric material **199** includes a slit **180** (not shown in FIG. 1C, as, in some embodiments, the slit is not utilized). In an exemplary embodiment, the slit **180** has utilitarian value in that it can enable insertion and/or removal of the magnet apparatus **160** from the housing made of elastomeric material **199**.

It is noted that magnet apparatus **160** is presented in a conceptual manner. In this regard, it is noted that in at least some embodiments, the magnet apparatus **160** is an assembly that includes a magnet surrounded by a biocompatible coating. Still further, in an exemplary embodiment, magnet apparatus **160** is an assembly where the magnet is located within a container having interior dimensions generally corresponding to the exterior dimensions of the magnet. This container can be hermetically sealed, thus isolating the magnet in the container from body fluids of the recipient that penetrate the housing (the same principle of operation occurs with respect to the aforementioned coated magnet). In an exemplary embodiment, this container permits the magnet to revolve or otherwise move relative to the container. Additional details of the container will be described below. In this regard, it is noted that while sometimes the term magnet is used as shorthand for the phrase magnet apparatus, and thus any disclosure herein with respect to a magnet also corresponds to a disclosure of a magnet apparatus according to the aforementioned embodiments and/or variations thereof and/or any other configuration that can have utilitarian value according to the teachings detailed herein.

With reference now to FIG. 1C, it is noted that the outlines of the housing made from elastomeric material **199** are presented in dashed line format for ease of discussion. In an exemplary embodiment, silicone or some other elastomeric material fills the interior within the dashed line, other than the other components of the implantable device (e.g., plates, magnet, stimulator, etc.). That said, in an alternative embodiment, silicone or some other elastomeric material substantially fills the interior within the dashed lines other than the components of the implantable device (e.g., there can be pockets within the dashed line in which no components and no silicone is located).

It is noted that FIGS. 1B and 1C are conceptual FIGS. presented for purposes of discussion. Commercial embodiments corresponding to these FIGS. can be different from that depicted in the figures.

Additional details of the plates, magnets, and housing made of elastomeric material will be described in greater detail below. First, however, additional functional details of the cochlear implant **100** will now be described.

FIG. 2A is a functional block diagram of a prosthesis **200A** in accordance with embodiments of the present invention. Prosthesis **200A** comprises an implantable component **244** configured to be implanted beneath a recipient's skin or other tissue **250** and an external device **204**. For example, implantable component **244** may be implantable component **100** of FIG. 1A, and external device may be the external device **142** of FIG. 1A. Similar to the embodiments described above with reference to FIG. 1A, implantable component **244** comprises a transceiver unit **208** which receives data and power from external device **204**. External device **204** transmits power and data **220** via transceiver unit **206** to transceiver unit **208** via a magnetic induction data link **220**. As used herein, the term receiver refers to any device or component configured to receive power and/or data such as the receiving portion of a transceiver or a separate component for receiving. The details of transmission of power and data to transceiver unit **208** are provided below. With regard to transceivers, it is noted at this time that while embodiments of the present invention may utilize transceivers, separate receivers and/or transmitters may be utilized as appropriate. This will be apparent in view of the description below.

Implantable component **244** may comprise a power storage element **212** and a functional component **214**. Power storage element **212** is configured to store power received by transceiver unit **208**, and to distribute power, as needed, to the elements of implantable component **244**. Power storage element **212** may comprise, for example, a rechargeable battery **212**. An example of a functional component may be a stimulator unit **120** as shown in FIG. 1B.

In certain embodiments, implantable component **244** may comprise a single unit having all components of the implantable component **244** disposed in a common housing. In other embodiments, implantable component **244** comprises a combination of several separate units communicating via wire or wireless connections. For example, power storage element **212** may be a separate unit enclosed in a hermetically sealed housing. The implantable magnet apparatus and plates associated therewith may be attached to or otherwise be a part of any of these units, and more than one of these units can include the magnet apparatus and plates according to the teachings detailed herein and/or variations thereof.

In the embodiment depicted in FIG. 2A, external device **204** includes a data processor **210** that receives data from data input unit **211** and processes the received data. The processed data from data processor **210** is transmitted by transceiver unit **206** to transceiver unit **208**. In an exemplary embodiment, data processor **210** may be a sound processor, such as the sound processor of FIG. 1A for the cochlear implant thereof, and data input unit **211** may be a microphone of the external device.

FIG. 2B presents an alternate embodiment of the prosthesis **200A** of FIG. 2A, identified in FIG. 2B as prosthesis **200B**. As may be seen from comparing FIG. 2A to FIG. 2B, the data processor can be located in the external device **204** or can be located in the implantable component **244**. In some embodiments, both the external device **204** and the implantable component **244** can include a data processor.

As shown in FIGS. 2A and 2B, external device **204** can include a power source **213**. Power from power source **213** can be transmitted by transceiver unit **206** to transceiver unit **208** to provide power to the implantable component **244**, as will be described in more detail below.

While not shown in FIGS. 2A and 2B, external device **204** and/or implantable component **244** include respective inductive communication components. These inductive communication components can be connected to transceiver unit **206** and transceiver unit **208**, permitting power and data **220** to be transferred between the two units via magnetic induction.

As used herein, an inductive communication component includes both standard induction coils and inductive communication components configured to vary their effective coil areas.

As noted above, prosthesis **200A** of FIG. 2A may be a cochlear implant. In this regard, FIG. 3A provides additional details of an embodiment of FIG. 2A where prosthesis **200A** is a cochlear implant. Specifically, FIG. 3A is a functional block diagram of a cochlear implant **300** in accordance with embodiments of the present invention.

It is noted that the components detailed in FIGS. 2A and 2B may be identical to the components detailed in FIG. 3A, and the components of 3A may be used in the embodiments depicted in FIGS. 2A and 2B.

Cochlear implant **300A** comprises an implantable component **344A** (e.g., implantable component **100** of FIG. 1) configured to be implanted beneath a recipient's skin or other tissue **250**, and an external device **304A**. External device **304A** may be an external component such as external component **142** of FIG. 1.

Similar to the embodiments described above with reference to FIGS. 2A and 2B, implantable component **344A** comprises a transceiver unit **208** (which may be the same transceiver unit used in FIGS. 2A and 2B) which receives data and power from external device **304A**. External device **304A** transmits data and/or power **320** to transceiver unit **208** via a magnetic induction data link. This can be done while charging module **202**.

Implantable component **344A** also comprises a power storage element **212**, electronics module **322** (which may include components such as sound processor **126** and/or may include a stimulator unit **322** corresponding to stimulator unit **122** of FIG. 1B) and an electrode assembly **348** (which may include an array of electrode contacts **148** of FIG. 1A). Power storage element **212** is configured to store power received by transceiver unit **208**, and to distribute power, as needed, to the elements of implantable component **344A**.

As shown, electronics module **322** includes a stimulator unit **332**. Electronics module **322** can also include one or more other functional components used to generate or control delivery of electrical stimulation signals **315** to the recipient. As described above with respect to FIG. 1A, electrode assembly **348** is inserted into the recipient's cochlea and is configured to deliver electrical stimulation signals **315** generated by stimulator unit **332** to the cochlea.

In the embodiment depicted in FIG. 3A, the external device **304A** includes a sound processor **310** configured to convert sound signals received from sound input unit **311** (e.g., a microphone, an electrical input for an FM hearing system, etc.) into data signals. In an exemplary embodiment, the sound processor **310** corresponds to data processor **210** of FIG. 2A.

FIG. 3B presents an alternate embodiment of a cochlear implant **300B**. The elements of cochlear implant **300B**

correspond to the elements of cochlear implant **300A** except that external device **304B** does not include sound processor **310**. Instead, the implantable component **344B** includes a sound processor **324**, which may correspond to sound processor **310** of FIG. 3A.

As will be described in more detail below, while not shown in the figures, external device **304A/304B** and/or implantable component **344A/344B** include respective inductive communication components.

FIGS. 3A and 3B illustrate that external device **304A/304B** can include a power source **213**, which may be the same as power source **213** depicted in FIG. 2A. Power from power source **213** can be transmitted by transceiver unit **306** to transceiver unit **308** to provide power to the implantable component **344A/344B**, as will be detailed below. FIGS. 3A and 3B further detail that the implantable component **344A/344B** can include a power storage element **212** that stores power received by the implantable component **344** from power source **213**. Power storage element **212** may be the same as power storage element **212** of FIG. 2A.

In contrast to the embodiments of FIGS. 3A and 3B, as depicted in FIG. 3C, an embodiment of the present invention of a cochlear implant **300C** includes an implantable component **344C** that does not include a power storage element **212**. In the embodiment of FIG. 3C, sufficient power is supplied by external device **304A/304B** in real time to power implantable component **344C** without storing power in a power storage element. In FIG. 3C, all of the elements are the same as FIG. 3A except for the absence of power storage element **212**.

Some of the components of FIGS. 3A-3C will now be described in greater detail.

FIG. 4A is a simplified schematic diagram of a transceiver unit **406A** in accordance with an embodiment of the present invention. An exemplary transceiver unit **406A** may correspond to transceiver unit **206** of FIGS. 2A-3C. As shown, transceiver unit **406A** includes a power transmitter **412**, a data transceiver **414A** and an inductive communication component **416**.

In an exemplary embodiment, as will be described in more detail below, inductive communication component **416** comprises one or more wire antenna coils (depending on the embodiment) comprised of multiple turns of electrically insulated single-strand or multi-strand platinum or gold wire (thus corresponding to coil **137** of FIG. 1B). Power transmitter **412A** comprises circuit components that inductively transmit power from a power source, such as power source **213**, via an inductive communication component **416** to implantable component **344A/B/C** (FIGS. 3A-3C). Data transceiver **414A** comprises circuit components that cooperate to output data for transmission to implantable component **344A/B/C** (FIGS. 3A-3C). Transceiver unit **406A** can receive inductively transmitted data from one or more other components of cochlear implant **300A/B/C**, such as telemetry or the like from implantable component **344A** (FIG. 3A).

Transceiver unit **406A** can be included in a device that includes any number of components which transmit data to implantable component **344A/B/C**. For example, the transceiver unit **406A** may be included in a behind-the-ear (BTE) device having one or more of a microphone or sound processor therein, an in-the-ear device, etc.

FIG. 4B depicts a transmitter unit **406B**, which is identical to transceiver unit **406A**, except that it includes a power transmitter **412B** and a data transmitter **414B**.

It is noted that for ease of description, power transmitter **412A** and data transceiver **414A/data transmitter 414B** are

shown separate. However, it should be appreciated that in certain embodiments, at least some of the components of the two devices may be combined into a single device.

FIG. 4C is a simplified schematic diagram of one embodiment of an implantable component 444A that corresponds to implantable component 344A of FIG. 3A, except that transceiver unit 208 is a receiver unit. In this regard, implantable component 444A comprises a receiver unit 408A, a power storage element, shown as rechargeable battery 446, and electronics module 322, corresponding to electronics module 322 of FIG. 3A. Receiver unit 408A includes an inductance coil 442 connected to receiver 441. Receiver 441 comprises circuit components which receive via an inductive communication component corresponding to an inductance coil 442 inductively transmitted data and power from other components of cochlear implant 300A/B/C, such as from external device 304A/B. The components for receiving data and power are shown in FIG. 4C as data receiver 447 and power receiver 449. For ease of description, data receiver 447 and power receiver 449 are shown separate. However, it should be appreciated that in certain embodiments, at least some of the components of these receivers may be combined into one component.

In the illustrative embodiments of the present invention, receiver unit 408A and transceiver unit 406A (or transmitter unit 406B) establish a transcutaneous communication link over which data and power is transferred from transceiver unit 406A (or transmitter unit 406B), to implantable component 444A. As shown, the transcutaneous communication link comprises a magnetic induction link formed by an inductance communication component system that includes inductive communication component 416 and coil 442.

The transcutaneous communication link established by receiver unit 408A and transceiver unit 406A (or whatever other viable component can so establish such a link), in an exemplary embodiment, may use time interleaving of power and data on a single radio frequency (RF) channel or band to transmit the power and data to implantable component 444A. A method of time interleaving power according to an exemplary embodiment uses successive time frames, each having a time length and each divided into two or more time slots. Within each frame, one or more time slots are allocated to power, while one or more time slots are allocated to data. In an exemplary embodiment, the data modulates the RF carrier or signal containing power. In an exemplary embodiment, transceiver unit 406A and transmitter unit 406B are configured to transmit data and power, respectively, to an implantable component, such as implantable component 344A, within their allocated time slots within each frame.

The power received by receiver unit 408A can be provided to rechargeable battery 446 for storage. The power received by receiver unit 408A can also be provided for distribution, as desired, to elements of implantable component 444A. As shown, electronics module 322 includes stimulator unit 332, which in an exemplary embodiment corresponds to stimulator unit 322 of FIGS. 3A-3C, and can also include one or more other functional components used to generate or control delivery of electrical stimulation signals to the recipient.

In an embodiment, implantable component 444A comprises a receiver unit 408A, rechargeable battery 446 and electronics module 322 integrated in a single implantable housing, referred to as stimulator/receiver unit 406A. It would be appreciated that in alternative embodiments, implantable component 344 may comprise a combination of several separate units communicating via wire or wireless connections.

FIG. 4D is a simplified schematic diagram of an alternate embodiment of an implantable component 444B. Implantable component 444B is identical to implantable component 444A of FIG. 4C, except that instead of receiver unit 408A, it includes transceiver unit 408B. Transceiver unit 408B includes transceiver 445 (as opposed to receiver 441 in FIG. 4C). Transceiver unit 445 includes data transceiver 451 (as opposed to data receiver 447 in FIG. 4C).

FIGS. 4E and 4F depict alternate embodiments of the implantable components 444A and 444B depicted in FIGS. 4C and 4D, respectively. In FIGS. 4E and 4F, instead of coil 442, implantable components 444C and 444D (FIGS. 4E and 4F, respectively) include inductive communication component 443. Inductive communication component 443 is configured to vary the effective coil area of the component, and may be used in cochlear implants where the exterior device 304A/B does not include a communication component configured to vary the effective coil area (i.e., the exterior device utilizes a standard inductance coil). In other respects, the implantable components 444C and 444D are substantially the same as implantable components 444A and 444B. Note that in the embodiments depicted in FIGS. 4E and 4F, the implantable components 444C and 444D are depicted as including a sound processor 342. In other embodiments, the implantable components 444C and 444D may not include a sound processor 342.

FIG. 5 represents a high level conceptual exemplary magnetic coupling arrangement according to an exemplary embodiment. Specifically, FIG. 5 presents the magnet apparatus 160 of the implantable component 100 having a longitudinal axis 599 aligned with the magnet 560 of the external device 142, along with a functional representation of the tissue 504 of the recipient located between the two components. All other components of the external device and implantable component are not shown for purposes of clarity. As can be seen, the magnet apparatus 160 as a north-south polar axis aligned with the longitudinal axis 599, and magnet apparatus 560 also has a north-south polar axis aligned with the longitudinal axis of that magnet apparatus. In the exemplary embodiment, owing to the arrangements of the magnets, the resulting magnetic field aligns the magnets such that the longitudinal axes of the magnets are aligned. In an exemplary embodiment, because the various coils of the devices are aligned with the various longitudinal axes of the magnets, the alignment of the magnets aligns the coils.

FIG. 6 presents an alternative embodiment, where the magnet apparatus 160 of the implantable component 100 has a north-south axis aligned with the lateral axis of the magnet apparatus, as can be seen. In this exemplary embodiment, the magnet 560 also has a north-south axis also aligned with the lateral axis of that magnet.

As can be inferred from FIGS. 1B and 1C, the magnet apparatus of the implantable component 100 is a disk magnet apparatus/has the form of a short cylinder. The magnet of the external device 142 can also have such a form. That said, in an alternative embodiment, the magnets can have another configuration (e.g., a plate magnet, a bar magnet, etc.). Moreover, in an alternative embodiment, two or more magnets can be used in the implantable device and/or in the external device. The magnets could be located outboard of the coil. Any arrangement of magnet(s) of any configuration that can have utilitarian value according to the teachings detailed herein and/or variations thereof can be utilized in at least some embodiments.

FIG. 7A presents a portion of the view of FIG. 1C (side view of FIG. 1B), showing the magnet apparatus 160

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sandwiched by plates **170** and **172**. All other components are removed for purposes of clarity. FIG. 7B depicts an rectangular-shaped dashed line structure, which conceptually represents a volume that is generally filled with an elastomeric material, such as silicone, thus conceptually representing the housing made from elastomeric material **199** of FIG. 1B. In an exemplary embodiment, the space is basically filled with silicone. That said, in an alternate embodiment, there are locations where there is no elastomeric material. FIG. 7B-7C present some examples, where the volume between the magnet apparatus **160** and the vertical dashed lines is devoid of silicone. (Note that these views represent only the sides of the magnet apparatus and housing with respect to the cross-section taken along the longitudinal axis of the implantable device **100**—the elastomeric material can be closer to the magnet apparatus on the lateral sides/away from the longitudinal axis of the implantable device **100**, thus still maintaining the position of the magnet apparatus **160**.)

In an exemplary embodiment, the elastomeric material surrounding the plates holds the plates in place against the magnet. In this regard, with reference back to FIG. 7A, as can be seen, the plates **170** and **172** are located a distance **D1** from each other. In an exemplary embodiment, distance **D1** corresponds to the thickness of the magnet (as differentiated from the width of the magnet, which corresponds to the diameter of a disc magnet, which can be a disk magnet, as measured on a plane normal to the longitudinal axis **599**). That is, in an exemplary embodiment, the plates are located in direct contact with the opposite faces of the magnet apparatus **160**. In an exemplary embodiment where the opposite faces of the magnet apparatus are parallel, the surfaces of the plates **170** and **172** facing each other are also parallel, as those surfaces are also flat surfaces. It is briefly noted at this time that while the embodiments of the plates detailed herein are presented in terms of circular disks having uniform flat surfaces on either side thereof, in an alternate embodiment, the plates can be of different configurations, especially with respect to the surfaces thereof facing away from one another. Briefly, FIG. 7D depicts an exemplary alternate embodiment, where the upper plate **170D** has a flat bottom surface, but a curved top surface. Note further that upper plate **170D** has an outer diameter that is smaller than that of the bottom plate **172**. Note also that the upper plate **170D** is offset relative to the longitudinal axis **599** of the magnet apparatus **160**. Any or all of these features can be utilized separately and/or together, on the upper plate and/or on the bottom plate. Additional details of the plates will be described below.

As noted above, the elastomeric material surrounding the plates holds the plates against the magnet apparatus **160**. That is, in an exemplary embodiment, the housing made from elastomeric material **199** is arranged such that when the magnet apparatus **160** is located between the plates, the elastomeric material can impart a downwards and upwards force, respectively, onto the plate **170** and plate **172**, thereby imparting a downward and upward force on to the opposite faces of the magnet apparatus **160**. FIG. 8 represents a conceptual diagram of a force profile **F1** applied by the resilience material of the housing to the plate **170** when the magnet apparatus **160** is located between the plates **170** and **172**. In an exemplary embodiment, an equal and opposite force **F1** is also present on the bottom surface of the plate **172**. In an exemplary embodiment, this imparts a compressive force onto the magnet apparatus **160**. That said, it is noted that in an alternate embodiment, the force profile **F1** can correspond to a zero force (in the absence of an external

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magnetic field). That is, an exemplary embodiment can entail a housing made of elastomeric material **199** that positions the plates **170** and **172** such that there is little to no compressive force onto the magnet apparatus **160**. Still further, in an exemplary embodiment, there can be a gap between the magnet apparatus **160** and one or both of the plates **170** and **172**, such that irrespective of the force profile **F1** in the absence of an external magnetic field, no compressive force is applied to the magnet apparatus **160**. That said, embodiments detailed herein will be presented in terms of a configuration where the housing made of elastomeric material **199** applies a compressive force through the plates onto the magnet apparatus **160** in the absence of an external magnetic field.

Referring now to FIG. 9, FIG. 9 depicts an exemplary scenario where an external magnetic field is applied to the magnet apparatus **160** while the magnet apparatus **160**, and thus the implantable component **100**, is implanted in a recipient at a location in the recipient corresponding to that which is where the implantable component would be implanted for normal use thereof (e.g., the magnet apparatus **160** can be located above the mastoid bone of the recipient and beneath the skin of the recipient for a cochlear implant). In an exemplary embodiment, the external magnetic field is that which results from an MRI machine during MRI imaging of the recipient's head (with the implantable component **100**, and thus the magnet apparatus **160**, implanted therein), where the magnetic field generated by the MRI machine interacts with the magnetic field of the magnet apparatus **160** to impart a significant torque onto the magnet apparatus **160**. In an exemplary embodiment, the torque is up to 0.38 Newton meters, and the MRI machine applies a magnetic field such that the implanted magnet apparatus **160** is subjected to a 3 T magnetic field. The explanation below refers to a 3 T magnetic field, but is applicable to any applied field, such as by way of example only and not by way of example, a field of 0.2 T, 1.5 T, 3 T, 4 T, 5 T, 6 T and 7 T or more in some embodiments.

In an exemplary embodiment, the magnetic field is generated by a bore MRI machine. That said, in some embodiments, the magnetic field is generated by an open MRI. The teachings detailed herein are applicable to any MRI that imparts a magnetic field onto the magnet of the magnet apparatus **160** that imparts a torque onto the magnet.

As can be seen from FIG. 9, in an exemplary embodiment, the implantable component **100** is configured such that the plates **170** and **172** are pushed apart from one another due to rotation of the magnet apparatus **160** as a result of the torque applied thereto due to the 3 T magnetic field. As can be seen, the magnet apparatus **160** rotates such that its longitudinal axis moves from its normal position (the position where the magnet is located in the absence of an external magnetic field—as seen in FIGS. 7A and 8, where the longitudinal axis **599** of the magnet apparatus **160** is at least generally normal to the major surface of the plates). Owing to the rotation of the magnet **160**, the magnet **160** is tilted between the plates **170** and **172**. This is the result of pushing the plates **170** and **172** away from each other. This is represented by the distance **D2** depicted in FIG. 9. As can be seen by visual inspection of FIG. 9 as compared to FIG. 7A, distance **D2** is larger than distance **D1**. In an exemplary embodiment, distance **D1** is 2.2 mm (corresponding to the thickness of the magnet **160**, which can have a 12 mm diameter (width)). In an exemplary embodiment, distance **D2** can be about 2.3 mm, 2.4 mm, 2.5 mm, 2.6 mm, 2.7 mm, 2.8 mm, 2.9 mm, 3.0 mm, 3.1 mm, 3.2 mm, 3.3 mm, 3.4 mm, 3.5 mm, 3.6 mm, 3.7 mm, 3.8 mm, 3.9 mm, 4.0 mm, 4.1 mm, 4.2 mm, 4.3 mm,

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4.4 mm, 4.5 mm, 4.6 mm, 4.7 mm, 4.8 mm, 4.9 mm, 5.0 mm or more or any value or range of values therebetween in about 0.01 mm increments (e.g., about 2.44 mm to about 4.37 mm, 3.89 mm, etc.). Still further, in an exemplary embodiment, the difference between D2 and D1 (D2-D1) is about 0.01 mm, 0.1 mm, 0.2 mm, 0.3 mm, 0.4 mm 0.5 mm, 0.6 mm, 0.7 mm, 0.8 mm, 0.9 mm, 1.0 mm, 1.1 mm, 1.2 mm, 1.3 mm 1.4 mm, 1.5, mm, 1.6 mm, 1.7 mm, 1.8 mm, 1.9 mm, 2.0 mm, 2.1 mm, 2.2 mm, 2.3 mm, 2.4 mm, 2.5 mm, 2.6 mm, 2.7 mm, 2.8 mm, 2.9 mm, 3.0 mm or more or any value or range of values therebetween in about 0.01 mm increments).

FIG. 9 shows the longitudinal axis 599 of the magnet 160 shifted from its normal position (599'). In an exemplary embodiment, shift from the normal position in degrees is about 5.0, 6.0, 7.0, 8.0, 9.0, 10.0, 11.0, 12.0, 13.0, 14.0, 15.0, 16.0, 17.0, 18.0, 19.0, 20.0, 21.0, 22.0, 23.0, 24.0, 25.0, 26.0, 27.0, 28.0, 29.0, 30.0, 31.0, 32.0, 33.0, 34.0, or 35.0 or more or any value or range of values therebetween in about 0.1 increments (e.g., about 11.3 to about 24.1 degrees, 15.3 degrees, etc.).

In an exemplary embodiment, owing to the housing made of elastomeric material 199, as the plates 170 and 172 are pushed apart from one another, the force applied to the outer surfaces of the plates by the material of the housing increases from the profile F1. The force on the outer surface of the plates will be considered in this explanation for clarity. It should be noted that the elastomeric material between the plates will exert a force on the inner surface of the plates. This force will act in the same direction as the force on the outside of the plates (i.e., toward the magnet). Hence, such can increase the effect described. In this regard, FIG. 10 presents a conceptual schematic representing a force profile F2 on the upper surface of the upper plate 170 resulting from the elastomeric material 199 having been stretched/displaced due to the expansion of the distance between the plates from D1 to D2, where, in an exemplary embodiment, an equal and opposite force profile is also located on the bottom surface of the bottom plate 172. The arrows of force profile F2 are presented longer than those of force profile F1 of FIG. 8, representing the fact that force profile F2 constitutes a larger force profile than that of FIG. 8.

Thus, in an exemplary embodiment, the increase in the distance between the plates increases the force profile on those plates imparted by the material of the housing. This increase in the force profile on the plates is in turn applied to the magnet 160 by the plates, as magnet 160 contacts the plates 170 and 172 (directly or indirectly, as will be described in greater detail below). The increase in the force profile counteracts the torque applied to the magnet 160 due to the 3 T magnetic field of the Mill machine. When the forces resulting from the torque applied to the magnet 160 are in equilibrium with the resulting force profile applied to the plates due to deformation of the elastomeric material of the housing, further rotation of the magnet 160 is prevented.

FIG. 11 provides an exemplary conceptual chart presenting a force (force on the plates) versus distance between plates curve, where point A corresponds to the location of the plates in a relaxed state (e.g., without magnet 160 located there between), point B corresponds to the force resulting from the magnet being located between the plates in the normal location without an external magnetic field (the force profile F1, where the magnet 160 itself pushes the plates away from each other), and point C representing the maximum plate separation resulting from the 3 T magnetic field. As can be seen, in the exemplary embodiment, the increase in forces is linear. FIG. 12 presents a force versus distance

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between plate curve for an alternate embodiment, where points A and B are located at the same location (the location of the plates in the relaxed state is the same with or without the magnet 160 being located therebetween—the plates provide a negligible, if not no force onto the magnet in the absence of an external magnetic field). As with the chart of FIG. 11, the curve is linear. FIG. 13 presents an alternate embodiment where the force is nonlinear with respect to the distance between the plates. It is noted that these charts are but examples with respect to force versus distance between plates curves. Other configurations of exemplary embodiments will result in other curves. Any relationship between force and distance between plates that will enable the teachings detailed herein and/or variations thereof to be practiced can be utilized in at least some embodiments.

An exemplary principle of operation of some exemplary embodiments will now be described in conceptual terms. It is noted that these principle of operations are but exemplary, and to the extent that embodiments can be practiced utilizing the teachings detailed herein and/or variations thereof that results in other principles of operations being utilized in a manner having utilitarian value, such other principles of operations can also be utilized to implement the teachings detailed herein. That said, FIG. 14 presents an exemplary conceptual arrangement with the plates 170 and 172 and the magnet 160 located in a conceptual housing 1499 made of elastomeric material having wall thicknesses T1 and T2 as seen, where the magnet 160 is not exposed to an external magnetic field. In some exemplary embodiments, the conceptual housing 1499 applies a compressive force onto the magnet through the plates 170 and 172 in the absence of an external magnetic field. In some exemplary embodiments, the conceptual housing 1499 does not apply compressive force onto the magnet through the plates in the absence of an external magnetic field. FIG. 15 represents the magnet 160 being subjected to an external magnetic field of 3 T, where the magnet 160 has rotated due to the torque applied thereto resulting from the magnetic field. As can be seen, the wall thicknesses of the housing 1499, T1' and T2', are thinner than that of T1 and T2 of FIG. 14, owing to the fact that the plates 170 and 172 have been pushed away from one another relative to that which was the case in FIG. 14 owing to the torque applied to the magnet 160. In essence, the housing has stretched, or, more accurately, the elastomeric material of the housing 1499 has stretched. Because the elastomeric material of the housing has a memory such that the housing 1499 seeks to return to the state at which it was in in FIG. 14 (with the wall thickness returning to T1 and T2, or at least to something close to T1 and T2 and/or less than T1' and T2', the force profile F2 is developed on the plates as detailed above, thus countering further rotation of the magnet. By way of example only and not by way of limitation, the effect of the housing 1499 on the plates 170 and 172 can be considered analogous to the principle of operation of a rubber band. In this regard, the elastomeric material of the housing 1499 imparts a compressive force onto the plates 170 and 172, where the compressive force increases with increased separation of the plates from each other due to the rotation of the magnet 160.

In an exemplary embodiment, the elastomeric material utilized to fabricate the housing is made of silicone MED4860 (from Nusil). In an exemplary embodiment, T1 is about 0.3 mm (which also includes 0.3 mm—all uses of about and substantially and other qualifiers also include the exact amount unless otherwise specified), and the maximum thickness of the housing, as measured parallel to the longi-

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tudinal axis of the magnet **599** at any location above and below the plates, is about 4 mm (which includes 4 mm or less).

It is noted that FIGS. **14** and **15** are simply conceptual figures. It is noted that the thicknesses are depicted as changing by an exaggerated amount. Moreover, it is possible that in at least some embodiments, the thickness **T2** may not change and/or may change less than the thickness **T1** (by ratio and/or in total), and/or vice versa.

FIG. **16A** represents an alternate embodiment that utilizes components located between the plates **170** and **172** to provide a reaction force against the rotation of the magnet **160**, more specifically, the embodiment of FIG. **16A** includes resilient components/elastomeric components **1610** located outboard of the magnet **160** between the plates **170** and **172**. In the embodiments of FIG. **16A**, resilient component **1610** is presented as springs extending from the bottom plate **172** to the top plate **170**. In an alternative embodiment, these can be pillars of silicone adhered to the surfaces of the plates. The pillars (springs or resilient components) can be arrayed uniformly (or non-uniformly) about the magnet. The number of resilient component **1610** can correspond to any number that can enable the teachings detailed herein and/or variations thereof to be practiced. Still further, in an exemplary embodiment, the resilient component **1610** can be a ring or a partial ring about magnet **160**. That is, the resilient component **1610** can be a single component. Any device, system, and/or method that can provide tensile force between the plates **1720** and **1722** that can enable the teachings detailed herein and/or variations thereof to be practiced, can be utilized in at least some embodiments.

It is noted that some exemplary embodiments can be practiced without utilizing an elastomeric material to interact with or otherwise provide reactive force on the plates, or at least without utilizing an elastomeric material that makes up the housing or the like of the implant **100**. The plates can be attached rigidly at a number of locations around the edge thereof. By way of example, in effect, the plate provides the rigid component and the spring component providing the restoring force.

Further, by way of example only and not by way of limitation, utilizing as a basis for discussion the device of FIG. **16A**, with reference now to FIG. **16B**, it can be seen that the magnet apparatus **160** and the plates **170** and **172** and the springs **1610** are located in a housing **1669**. In this exemplary embodiment, the housing **1669** is a housing that also encompasses stimulator unit **122**, while in other embodiments, the housing does not encompass stimulator unit **122** and/or only encompasses the plates, the magnet apparatus and the associated components. The embodiment of FIG. **16B** is depicted as having a housing **1669** including the stimulator unit **122** as that will provide a larger footprint/area to react against any torque induced into the system. Any housing arrangement that will enable the teachings detailed herein and/or variations thereof to be practiced can be utilized in at least some embodiments.

In an exemplary embodiment, the housing **1669** is a rigid housing (e.g., it can have a rigidity of that of the plates or more or less). Additional details of this will be described below. As can be seen in FIG. **16B**, there are two rails that extend from the bottom portion of the housing **1669** to the top portion of the housing **1669**, which rails extend through plates **170** and **172**. In an exemplary embodiment, the arrangement is such that the relationship between the rails **1655** and the plates is such that the plates move with translational motion along the rails **1655** and cannot sub-

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stantially move (e.g., rotate) to a position where they are no longer parallel to each other. This can be achieved via close-fitting holes through the plates relative to the rails **1655**. Alternatively and/or in addition to this, extension tubes can be located on the plates in a manner that provides additional reaction torque against any rotation of the plates. Here, the springs **1610** provide a reaction force against the plates **170** and **172**, moving away from each other, or at least plate **170** moving away from plate **172** in the case where plate **172** is fixed to the bottom surface of the housing **1669**, in the presence of a magnetic field that imparts a torque onto the magnet apparatus **160**. The plates operate, in at least some embodiments, according to the same general principles detailed herein, except that instead of utilizing the elastomeric material of the housing to provide a force against the plates moving away from each other, the housing does not provide a force against the plates, but instead the springs **1610** provides the entire force. In an exemplary embodiment, there is utilitarian value with respect utilizing a rigid housing in the sense that the rigid housing can hold the rails **1655** in a proper position/properly aligned so that the system can operate in accordance to the principles detailed herein.

It is noted that in an alternate embodiment, compression springs instead of or in addition to the extension springs can be utilized. The compression springs can be located between the plate(s) and the housing **1669** wall(s).

FIG. **16C** depicts an alternate embodiment utilizing concepts similar to those of FIG. **16B**. In this regard, a plate **172L** is utilized that extends from the stimulator unit **122** to the magnet apparatus **160**. In this exemplary embodiment, the length of the plate **172L** provides sufficient reaction against any torque imparted into the system resulting from the magnetic field applied to the magnet apparatus **160**. Housing **1669X** is presented as being a rigid housing concomitant with housing **1660** of FIG. **16B**. However, in alternate embodiments, housing **1669X** can be a housing made of an elastomeric material. In such an exemplary embodiment, according to an exemplary embodiment thereof, there is sufficient space provided for the plate **170** to move accordingly. That said, in an alternate embodiment, the elastomeric material can act in combination with the springs **1610**.

FIG. **16D** presents an alternate embodiment utilizing concepts similar to those of FIG. **16B**. Here, the system utilizes a long plate **170L** on the top and a long plate **172L** on the bottom. These plates extend from the stimulator unit **122** to the magnet apparatus **160** as can be seen. In an exemplary embodiment, owing to the fact that the plates have a modicum of resiliency over the long span owing to their length, while having localized rigidity in the locations proximate to the magnet apparatus **160**, the arrangement of FIG. **16D** can be used to practice the principles detailed herein and/or variations thereof. While it will be understood that the configuration of **16D** may not result in the plates being parallel to each other in some instances, in an exemplary embodiment, plate **170L** can be a composite plate such that the portion that interfaces with magnet **160**, is permitted to rotate relative to the other portions of plate **170L** when the plates separate from each other owing to the torque applied to the magnet apparatus **160**, so that the portion that interfaces with magnet **160** remains parallel. In an exemplary embodiment, portion **170L1** can be hinged to portion **170L2**, and an arrangement can be provided that imparts a force onto **170L1** as the plates are pushed apart to force the portion **170L1** to remain at least generally parallel to **170L**. Again, housing **1669X** can be a rigid housing or a flexible housing.

Any arrangement that can enable the teachings detailed herein and/or variations thereof to be practiced can be utilized in at least some embodiments.

In this regard, the plates have been shown flat even when under load such as in FIG. 15. Some embodiments utilize plates which have some compliance so the plates bend to a limited extent when under load. In some embodiments, this will put the plate in tension such that there is a restoring force tending to make the plate substantially flat again. This unbending force from the plate will add to the force on the magnet apparatus.

In view of the above, it will be understood that in an exemplary embodiment, there is an implantable medical device, such as a cochlear implant, or any other type of medical device that utilizes an implantable magnet (irrespective of what the implantable magnet is used for/irrespective of whether or not the implantable magnet is utilized to retain an external component to the recipient), comprising a magnet apparatus, such as magnet 160 detailed above by itself or encased in a housing (e.g., a titanium housing) and/or coated in a biocompatible material, and a body (e.g., body 199/housing conceptually represented by element 1499 as detailed above) encompassing the magnet, the body made of an elastomeric material, such as silicone (biocompatible/implantable), rubber (biocompatible/implantable rubber), or incorporating resilient elements (e.g. springs) as part of the housing or any other material, such as a polymer body that will enable the teachings detailed herein and/or variations thereof. The implantable medical device resists rotation of the magnet relative to the body in at least one plane when subjected to an externally generated magnetic field due to a component (e.g., one or both of the plates 170 and 172) relative to which the magnet apparatus is slidable, wherein the component located within the body.

It is noted that by slidable, this means that the magnet changes a global position relative to the component. This as contrasted to the magnet revolving/spinning relative to the plates, where the magnet is in the same position, except that points on the magnet's surface are at a different location. By analogy, a car tire can slide on ice when the car tire moves location. A car tire spinning on the ice is not sliding across the ice.

In an exemplary embodiment, the medical device includes a plurality of separate structural components (e.g., plates 170 and 172) of greater rigidity than the body/material of the body, at least partially embedded in the body, wherein one of the plurality of structural components corresponds to the component relative to which the magnet apparatus slides, and wherein the structural components resists rotation of the magnet apparatus within the body, as detailed above (which resistance is achieved through interaction between the plates and the magnet apparatus). In an exemplary embodiment, the medical device includes a first structural component and a second structural component (again, plates 170 and 172), where the first and second structural components collectively are sandwiching the magnet apparatus, wherein the structural components resist rotation of the magnet apparatus in at least one plane within the body. In this regard, in an exemplary embodiment, the structural components resist rotation of the magnet apparatus in the plane used for the cross-sectional view shown in FIGS. 7A, 8, 9, etc. That is, a plane on which the longitudinal axis of the magnet 160 lies.

In an exemplary embodiment, the plates are about  $\frac{1}{2}$ , 1, 1.5, 2 or 3 or more orders of magnitude more rigid than the body. By way of example only and not by way of limitation,

silicone has a young's modulus of 0.001 to 0.05 GPa while PEEK has a young's modulus of 3.6 GPa.

By "resists rotation," as detailed herein the medical device is configured to permit a modicum of rotation of the magnet apparatus. Indeed, in at least some exemplary embodiments, some initial rotation is required so as to push the plates apart thereby creating the above-detailed force F2, so as to resist further rotation. Accordingly, in an exemplary embodiment, the first and second plates, which are separate from one another, are arranged such that the magnet apparatus is restrained from rotating beyond an initial amount within the body by the first and second plates, this being encompassed by the configuration that resists rotation as detailed herein.

Note further that in an exemplary embodiment of this exemplary embodiment, the magnet alone and/or the magnet coated with another material and/or the magnet located in a container making up the magnet apparatus can revolve relative to the longitudinal axis thereof. Accordingly, in an exemplary embodiment, the medical device is configured to not resist revolution of the magnet apparatus and/or the magnet, at least about one axis.

It is further noted that in an exemplary embodiment, the medical device is configured to resist movement of the magnet apparatus in all three directions of the Cartesian coordinate system. That said, in an alternate embodiment, the medical device is configured to resist movement of the magnet apparatus in only one or two directions of the Cartesian coordinate system. Corollary to this is that in an exemplary embodiment, the medical device is configured to resist rotation of the magnet apparatus about all three directions of the Cartesian coordinate system. That said, in an alternate embodiment, the medical device is configured to resist rotation of the magnet apparatus about only one or two directions of the Cartesian coordinate system.

Still further, as seen in FIG. 7A, the magnet apparatus has a width and height (e.g., the width is the long axis (largest diameter) of a circular magnet, and the height is the short axis of the circular magnet), wherein the height is less than the width, and the first plate 170 is located on a top side of the magnet apparatus, and the second plate 172 is located on a bottom side of the magnet apparatus opposite the top side, wherein the plates extend in a direction normal to the direction of the height (normal to the direction of the longitudinal axis of the magnet).

Corollary to this is that in an exemplary embodiment, the plates have a width and a height, wherein the height is less than the width, the width of the plates is greater than the width of the magnet apparatus, and the width of the plates is at least about parallel to the width of the magnet apparatus (consistent with FIG. 7A). As can be seen in the figures, one or both of the plates can extend past outer peripheries of the magnet apparatus with respect to a direction parallel to the width of the magnet apparatus.

In view of FIGS. 7B and 7C and 16, in an exemplary embodiment, an elastomeric material is located at opposite locations relative to the height direction of the magnet apparatus, and the elastomeric material that is located at opposite locations is located between the first plate and the second plate relative to the direction of extension of the height of the magnet apparatus. In an exemplary embodiment, the aforementioned elastomeric material can correspond to the elastomeric material of the body encompassing the plates (the housing 199). In an exemplary embodiment, the aforementioned elastomeric material can correspond to material separate from the material of the body (spring



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material, separate silicone where the body is also silicone, springiness built into the plates, etc.).

In an exemplary embodiment, the elastomeric material of the body (housing 199) resists movement of the first plate away from the second plate due to rotational torque applied to the magnet apparatus by the external magnetic field, thereby resisting rotation of the magnet apparatus. Again, the term “resists” encompasses a modicum of movement of the plates away from one another (and note that movement of the first plate away from the second plate also includes movement of the second plate away from the first plate as well, providing that there is movement of the first plate away from the second plate).

As noted above, in an exemplary embodiment, the magnet apparatus comprises a magnet located in a container, wherein the magnet is free to revolve relative to the container. FIG. 17 provides an exemplary schematic of such an exemplary environment, depicting magnet apparatus 160 (and, accordingly, any disclosure herein of magnet 160 corresponds to a disclosure of magnet apparatus of FIG. 17), including container 160' and magnet 160". FIG. 17 depicts magnet 160" subjected to an external magnetic field that imparts a torque thereon about an axis normal to the longitudinal axis 599 of the magnet 160", the torque represented by arrow 17T, causing the magnet to rotate about the axis normal to the longitudinal axis 599 of the magnet. The torque 17T depicted in FIG. 17 may represent the entire torque imparted on the magnet 160" by the external magnetic field or the component of the entire torque that causes the magnet to rotate—i.e. the component of the imparted torque that is centered about an axis normal to the longitudinal axis 599 of the magnet 160". The rotation of the magnet 160" is limited by the inner walls of container 160', and the torque applied to the container 160' by the magnet 160" is opposed by the plates as detailed herein, which are not shown in FIG. 17, but the function thereof is represented by arrows 17A and 17B, which applies the counter torque to the magnet, thereby resisting the torque 17T. However, the magnet 160" is configured to revolve about a longitudinal axis 599, even though the magnet is restrained from rotating beyond that permitted by the plate/housing assembly. In this regard, FIGS. 18A-18C depict an exemplary revolution of magnet 160" within container 160', where the container 160' remains stationary in each of the FIGS., but the magnet 160" revolves about axis 599. It is further noted that in this exemplary embodiment, the magnet 160" is a magnet having the north-south pole on the lateral sides of the magnet (i.e., the pole is aligned normal to the longitudinal axis 599). In an exemplary alternative embodiment, the magnet 160" can be a magnet having the north-south pole axis aligned with the longitudinal axis.

Accordingly, in an exemplary embodiment, the magnet apparatus comprises a magnet 160" located in a container 160', wherein the magnet is free to revolve relative to the container.

In an exemplary embodiment, the elastomeric material of the body extends around a majority of a circumference of the container in face to face relationship with the circumference of the container. By “face to face relationship,” it is meant that there is no other component of the implantable component 100 in between the elastomeric material and the container, such as a chassis or the like. In an exemplary embodiment, the silicone of the silicone body extends completely around the magnet apparatus in face to face relationship with the circumference of the magnet apparatus.

It is noted that in an exemplary embodiment, the container can include a low friction coating such as PTFE and/or a

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lubricant, such as an oil or the like, that reduces friction between the magnet 160" and the inner surface of the container 160'. Alternatively or in addition to this, the magnet apparatus 160 can utilize ball bearings or an axle with bushes, or the like. Indeed, in an exemplary embodiment, this can prevent substantially all (including all) rotation of the magnet 160" relative to the container 160', while permitting the magnet 160" to revolve relative to the container 160'. FIG. 19 depicts such an exemplary embodiment.

FIG. 20 depicts an exemplary embodiment of a plate 172, depicting a side view (top) and a top view (bottom). As can be seen, in an exemplary embodiment, the plate 172 has holes 173 into which the silicone material of the body (housing) can enter, thereby interlocking the elastomeric material with the plate. The configuration of plate 172 of FIG. 20 can be used as plate 170 as well.

It is noted that while in some embodiments, the holes 173 extend completely through the plate 172, in an alternate embodiment, the holes 173 only extended a portion of the way through the plate 172, so as to preserve a smooth surface on one side of the plate (e.g., the side facing the magnet). Still further by way of example, the holes 173 can be dovetailed or the like, so that the elastomeric material, during a molding process, can flow into the holes and then be quasi trapped therein. It is noted that while the embodiment of FIG. 20 presents an abundance of holes 173, alternate embodiments may utilize fewer holes 173. Alternatively, some embodiments may utilize more holes than those depicted in FIG. 20.

Note further that while the arrangement of holes 173 depicted in FIG. 20 corresponds to an array of holes located across the entire surface of the plate 172, in some alternate embodiments, the holes are more specifically located. In an exemplary embodiment, the holes can be arrayed about the outer periphery of the plate 172. This can have utilitarian value in embodiments where, for example, the holes 173 extend all the way through the plate 172, and it is desired to have a smooth surface at locations inboard of the holes along which the magnet apparatus will slide relative to the plate. Corollary to this is that there can instead be utilitarian value to having the holes 173 located in the center portion of the plates, where the tips of the magnet apparatuses do not reach because the rotation thereof is limited. Indeed, in an exemplary embodiment, this can permit maximum stretchability of the elastomeric material about the plates, because the elastomeric material is only anchored to the plates at the center. That said, in some embodiments, such may not have utilitarian value, and the former arrangement can be applied so as to permit minimum stretchability of the elastomeric material about the plates (because the elastomeric material is anchored to the plates about the periphery). Alternatively, combinations can exist where the holes on the outer periphery extend all the way through the plate, and the holes inboard thereof only extend a portion of the way through the plate, or visa-versa, etc.

Note further that the holes do not have to be completely surrounded holes, as seen in FIG. 21, where holes 174 are arrayed about the periphery (not all holes are depicted).

Any combination of holes that can enable the teachings detailed herein and/or variations thereof to be practiced can be utilized in at least some exemplary embodiments. This includes by way of example and not by way of limitation, tracks, channels or notches formed in the outward facing surface of the plate(s) with a dovetail groove or overhang that mechanically engages with the elastomeric housing.

In an exemplary embodiment, the plates can be made of PEEK, and can have a 0.3 mm thickness (the dimension of

the top reproduction of **172** in FIG. **20**) and a spanwise diameter (the dimension of the bottom reproduction of **172** in FIG. **20**) of 19 mm. Larger or smaller plates can be utilized. For example, the plates can have a thickness ranging from 0.1 mm to 0.5 mm, 0.2 mm to 0.4 mm or 0.25 to 0.35 mm and a spanwise diameter ranging from 15 mm to 24 mm, 16 mm to 23 mm or 17 mm to 21 mm. Still further, while the embodiments depicted in the FIGS. depict circular plates, alternative embodiments can utilize plates having oval shaped or generally rectangular (including square) shaped plates (with respect to the view looking at the surface facing towards or away from the magnet apparatus). Also, plates having complex boundaries can be utilized (star shapes, combination of rectangular and circular shapes, etc.). Indeed, the shapes of the plates can be tailored to achieve a given performance feature, as the shape of the plate will impact the resistance to separation of the plates away from one another for a given torque applied to a given magnet, all other things being equal. Still further, the bottom plate can be of a different configuration than the top plate.

In an exemplary embodiment, the plates can be made of any nonmagnetic material. Still further, and an exemplary embodiment, the plates can be made of any material that is conducive to the transfer of the magnetic flux generated by the magnet of the magnet apparatus **160** through the plates. Still further, any material or configuration of the plates that is conducive to the use of the coils **137** can be utilized.

In an exemplary embodiment, the plates are made from PTFE, PPSU, ceramic, or other materials or combinations of these materials. It is further noted that in an exemplary embodiment, the elastomeric body is molded about the plates. Thus, in an exemplary embodiment, the implantable component **100** is configured such that the plates are not removable from the body except in a scenario where the body is purposely being destroyed.

As noted above, the plates do not have to have parallel surfaces. While in some embodiments, the surface facing the magnet can be a flat surface, in other embodiments, the surface facing the magnet can be curved. Indeed, in an exemplary embodiment, curvature can be utilized to achieve a nonlinear "force" to "distance between plates" curve irrespective of the material properties of the elastomeric material utilized with the plates. Such an exemplary embodiment is seen in FIG. **22**, where plates **170X** are utilized. In an exemplary embodiment, because of the curved surfaces of plates **170X**, the more that the magnet **160** rotates, the resistance to the rotation thereof owing to the curvature of the surface increases in a non-linear manner for a given plate separation.

In an exemplary embodiment, a flat surface is utilized on one of the bottom or top plates, so as to provide stability to the magnet (e.g., to reduce any tendencies of the magnet **160** to rock owing to the fact that curved surfaces support the magnet), while a curved surface is utilized with one the other of the plates so as to achieve the above noted nonlinear force curve.

That said, in an alternate embodiment, the magnet is contoured to the curves. In this regard, FIG. **23A** depicts magnet apparatus **160X**, which has an upper surface and a lower surface that is contoured to the negative of the curved surfaces of the plates **170X**. In an exemplary embodiment, magnet apparatus **160X** is rotationally symmetric about the longitudinal axis thereof (i.e., it has bowl-like depressions on either side of the magnet apparatus). In an exemplary embodiment, this can have utilitarian value in that the contact between the magnet apparatus **160X** and the plates **170X** is always located at the outboard portions of the

magnet **160X** during rotation of the magnet **160X** relative to the plates **170X** (as opposed to possible embodiments of the embodiment of FIG. **22**).

FIG. **23B** depicts magnet apparatus **160 X** in conjunction with plates **170Y** and **170X**. Plate **170Y** includes the magnet apparatus contact surface corresponding to that of plate **170X**, except with the additional feature that the plate **170Y** extends further away from the longitudinal axis of the system than that of plate **170X**. In an exemplary embodiment, this could have utilitarian value with respect to the fact that the bottom plate **170X** is supported by the mastoid bone (in the example of a cochlear implant or other medical device having an inductance coil located thereabove), albeit through the body **199**, while the top plate **170Y** is not supported by any structure of the human body (or supported by soft tissue—skin, fat muscle). In this regard, the forces resulting from the application of the torque to the magnet apparatus are reacted against by bone on the bottom. Thus, the "footprint" of the bottom plate **170X** can be smaller than that of the top plate **170Y**, at least in some embodiments.

Corollary to the concept of FIG. **23B** is seen in FIG. **23C**, which uses flat parallel surfaces for the locations where the magnet apparatus will slide relative to the plates, but includes a plate **170Z** that uses canted surfaces for the portions that do not come into contact with the magnet apparatus **160** during rotation of the magnet. These canted surfaces can be utilitarian in that the plate **170Z** can be contoured to the outer geometry of the body of the implantable component **100**, to the extent that the body of the implantable component **100** slopes downward from the center to the sides. By canting the plate **170Z** as seen, a wider footprint can be achieved, while also permitting the implantable component to have a lower profile relative to that which would be the case if a perfectly flat plate having a similar footprint is utilized. Further as can be seen, the plate **170Z** need not be symmetric about its longitudinal axis.

As noted above, not all of the surface of the plates is sliding surface. Accordingly, an exemplary embodiment, such as seen in FIG. **23D**, includes plates **1700** and **1720** (the magnet apparatus **160** has been removed for clarity) that include bumpers **178** that align the magnet upon its return to the relaxed/no torque state after rotating due to exposure to the external magnetic field. The bumpers **178** can prevent the magnet from moving to a location beyond which is deemed permissible. FIG. **23E** depicts an alternate embodiment, where plates **1701** and **1721** include tracks **179** that guide the magnet as it rotates, thus ensuring, or at least reducing the likelihood that the magnet will move to a location that is less utilitarian when subjected to the magnetic field and were after the magnetic field is removed (such functionality is also achievable in the embodiments utilizing the bumpers **178** in at least some embodiments). Note further that while the tracks and bumpers detailed herein are presented in terms of fixed components, these components can be configured to move with the magnet. Indeed, in exemplary embodiments, the magnet can have a system akin to a rack and pinion system that permits the magnet to move according to the teachings detailed herein while also preventing the magnet from moving outside the local geographic coordinates of the plate system.

It is noted that the exemplary embodiments presented in FIGS. **23A-23E**, as with all embodiments herein, are presented in terms of concept. Variations from the specific disclosure herein can be practiced while achieving utilitarian value according the teachings detailed herein. To be clear, any device, system and/or method that can enable any of the

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teachings detailed herein and/or variations thereof to be practiced can be utilized at least some embodiments.

Any device, system and/or method of enabling the teachings detailed herein and/or variations thereof utilizing one or more structures (e.g., the plates) located in an elastomeric body can be utilized in at least some embodiments.

In view of the above, in an exemplary embodiment, there is an implantable medical device, such as any of those detailed herein and/or variations thereof, including a magnet, such as any of the magnets detailed herein and/or variations thereof, and a body encompassing the magnet, again such as any of the bodies detailed herein and/or variations thereof. In this exemplary embodiment, the implantable medical device includes structural components in the body configured to move away from one another upon initial rotation of the magnet relative to the body when the magnet is subjected to an externally generated magnetic field, thereby limiting rotation of the magnet beyond the initial rotation.

Also, in an exemplary embodiment, there is an implantable medical device, such as any of those detailed herein and/or variations thereof, including a magnet and a body encompassing the magnet. The implantable medical device includes structural components in the body configured to move away from one another due to torque applied to the magnet when the magnet is subjected to an externally generated magnetic field, thereby resisting rotation of the magnet at least beyond an initial rotation.

In an exemplary embodiment of these exemplary embodiments, the implantable medical device is configured to resist movement of the structural components away from one another. In an exemplary embodiment, the movement away of the structural components from one another tensions an elastomeric material making up at least a portion of the body, thereby limiting further movement of the structural components away from one another, which in turn limits further rotation of the magnet beyond any initial rotation.

Note further, in an exemplary embodiment, the structural components include surfaces facing one another in between which the magnet is located. The rotation of the magnet applies a force in a first direction against a first surface of one of the structural components and a force in a second direction against a second surface of one other of the structural components, thereby exerting forces on the components pushing the components away from one another, which force is at least partially resisted by the body, thereby limiting rotation of the magnet. Also, in an exemplary embodiment, the magnet is part of a magnet apparatus, and the implantable medical device is configured such that the magnet apparatus is slidable against the structural components, thereby encouraging rotation of the magnet relative to the structural components when the magnet is subjected to the externally generated magnetic field, relative to that which would exist with a configuration where the magnet apparatus was not slidable against the structural components.

Further, in an exemplary embodiment, the structural components comprise plates that sandwich the magnet, wherein torque applied to the magnet that imparts the rotation of the magnet imparts a camming action on the plates, thereby driving the plates away from one another, which camming action is counterbalanced when the plates have reached an equilibrium condition due to resistance to movement of the plates by the body.

As noted above, in at least some embodiments, there is utilitarian value with respect to enhancing the slideability of the magnet apparatus **160** relative to the plates. In this

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regard, in at least some embodiments, the surfaces facing the magnet apparatus/surfaces that contact the magnet apparatus are low friction surfaces. Alternatively and/or in addition to this, the surfaces of the magnet apparatus that contact the plates are also low friction surfaces. In an exemplary embodiment, a material that enhances slideability between the components can be utilized.

In at least some embodiments, the force profiles on the plates, or, more accurately, the change in the force profiles on the plates, due to movement of the plates away from one another, can be tuned by varying various properties of the plate-magnet-body combination. In an exemplary embodiment, the size of the plates (e.g., span) can be different depending on the desired change in the force profile. Alternatively and/or in addition to this, the elastomeric material making up the body can have different elastic modulus. Alternatively and/or in addition to this, the stiffness of the plates can be changed. It is noted that in an exemplary embodiment, the stiffness can be varied by changing the thickness of the plate while using the same material, changing the material of the plate while maintaining the same thickness, or changing the material and thickness of the plate, all changes being relative to a given baseline (as is the case with all changes detailed herein). Still further, as detailed above, plates having different geometries can be utilized. With respect to the embodiment of FIG. 7D, the plate **170D** will be less rigid at the outboard locations in a non-linear manner, owing to the fact that the thickness of the plates increases with distance towards the inboard location. That said, in an alternative embodiment, the structure of the plates can be such that the thickness of the plates thins with location closer to the inboard location.

Any arrangement of plates that can be utilized to implement the teachings detailed herein and/or variations thereof can be utilized in at least some embodiments.

With reference to FIG. 1B, as noted above, in an exemplary embodiment, the implantable component **100** includes a slit **180** configured to provide access through the exterior of the implantable component **100** to the location between the plates **170** and **172**. Thus, according to an exemplary embodiment, there is an implantable medical device, such as a cochlear implant, or other medical device that utilizes a magnet, for whatever reason, comprising a magnet and a body encompassing the magnet, wherein the silicone body has a slit configured to enable passage of the magnet therethrough. Accordingly, an exemplary embodiment includes a side entry pocket for the magnet apparatus.

More specifically, as can be seen in FIG. 24, which corresponds to an exploded view of a portion of the structure shown in FIG. 1C above, slit **198**, which corresponds to slit **180** of FIG. 1B, in some embodiments, is located in a side wall of the housing made of elastomeric material **199**. The slit **198** leads through the elastomeric material of the housing made thereof to a location between the plates **170** and **172**. In an exemplary embodiment, in its relaxed state, the slit has a major axis that is at least about the width of the magnet apparatus **160**, whereas the minor axis of the slit can be negligible, if not zero. That is, owing to the resiliency of the elastomeric material from which the housing is made, the slit **198** can be expanded to an expanded state so as to provide an opening of sufficient size to slide the magnet apparatus **160** into the housing and through the slit **198** to the location in between the plates.

Thus, with reference to FIG. 24, in an exemplary embodiment, the medical device includes a first surface and a second surface of an anti-rotation apparatus (e.g., plates **172** and **170**), wherein the magnet is located between the first

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surface and the second surface, and wherein a path exists from ends of the surfaces to the slit **198** through which the magnet can travel to reach the slit **198**.

It is noted that in some embodiments, the slit **198** is not provided in the implantable component **100** when implanted in the recipient. In an exemplary embodiment, the slit is provided in the implantable component at the time that the magnet is needed to be removed, via a surgery procedure. Accordingly, in an exemplary embodiment, there is a method of removing the magnet, which entails accessing the implantable component **100** while the implantable component is implanted in a recipient via a surgical procedure, optionally cutting into the body to form the slit **198**, or opening the slit **198** if already present (and closed), removing the magnet apparatus **160**, optionally temporarily closing the slit or otherwise sealing the slit, or replacing the magnet with a non magnetic blank (e.g., a dummy magnet) of similar outer dimensions, conducting an Mill method, reaccessing the implantable component **100**, reopening the slit formed therein if the optional temporary closing thereof was executed, replacing the magnet apparatus **160**, and closing the slit or otherwise sealing the slit (which closing/sealing can be a compost according to the teachings detailed below in at least some embodiments). Note further that in an exemplary embodiment, the implantable component **100** can include an embryonic slit. That is, the implantable component can include an area that is depressed or otherwise thin relative to other components, which area is proximate a path through the body to a location between the plates. Because the section is relatively thin, it will be relatively straightforward for the surgeon to cut through the thinned area to reach the path. Alternatively and/or in addition to this, the body can be marked or otherwise provided on the outside with a curve or a line (dye or with a raised or depressed area) indicating to the surgeon where he or she should cut to form the slit.

In an exemplary embodiment, the aforementioned features regarding the embryonic slits and/or markings can be molded into the silicone.

Now with reference to FIG. **25**, which depicts a view looking from the right side of FIG. **24** down the longitudinal axis of the implantable component **100**, with the top plate **198** removed for clarity, in an exemplary embodiment, the slit **198** includes two opposite surfaces **197A** and **197B**, the two opposite surfaces extending along the major axis of the slit (the axis parallel to the horizontal of FIG. **25**). The two opposite surfaces are level in a plane extending normal to a thickness direction (the vertical direction of FIG. **25**) of the magnet (when the slit is in the relaxed position). Further, the two opposite surfaces **197A** and **197B** are smooth, and the two opposite surfaces are in close proximity to one another (again, in the relaxed state). In an exemplary embodiment, the opposite surfaces **197A** and **197B** are in such close proximity to one another that they contact one another, again in the relaxed state. That said, in an alternative embodiment, the opposite surfaces are about 0.1, 0.2, 0.3, 0.4, 0.5, 0.6, 0.7, 0.8, 0.9 1.0, 1.1, 1.2, 1.3, 1.4, 1.5 mm or more away from each other in the relaxed state.

In an exemplary embodiment, the implantable component **100** is configured such that the two opposite surfaces **197A** and **197B** are urged towards each other, sometimes such that the surfaces contact one another. In an exemplary embodiment, this can be achieved via the general resilient/elastomeric nature of the material of the housing. Alternatively and/or in addition to this, this can be achieved via a spring embedded in the elastomeric body. In an exemplary embodiment, the implantable component **100** is configured such

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that the two opposite surfaces **197A** and **197B** are maintained in contact with each other. In an exemplary embodiment, this can be achieved via the general resilient/elastomeric nature of the material of the housing. Alternatively and/or in addition to this, this can be achieved via a spring **196** embedded in the elastomeric body, as conceptually depicted in FIG. **26**, where the oval-shaped spring **196** has a memory that drives the spring **196** to have minor axis as short as possible (i.e., the upper and lower portions desire to head towards each other). Still further, by way of example only and not by way of limitation, this can be achieved via one or more sutures (applied after the magnet apparatus is inserted into the slit). Further, adhesives can be utilized to close the slit. Also, in an exemplary embodiment, a tongue and groove fit can be utilized, such as seen in FIGS. **27A**, **27B** and **27C**, depicting a cross-sectional view of the slit **198** taken on a plane normal to the view of FIG. **25** in the vertical direction, where the top structure corresponds to the upper lip/surface of the slit, and the bottom structure corresponds to the lower lip/surface of the slit or vice versa. FIGS. **27B** and **27C** depict interference fits, with FIG. **27C** depicting a dovetail fit.

In an exemplary embodiment, the slit **198** can be configured with a structure corresponding to a zip lock structure utilized in sandwich bags or sterile bags of the like.

Accordingly, in an exemplary embodiment, the slit is held at least one of closed or constrained against further opening using at least one of sutures, an interference fit between two opposite sides of the slit, or a spring embedded in the silicone body.

It is noted that any of these manners of closing or otherwise providing a force against the slit **198** from opening further can be combined with each other. Any device, system, and/or method that will enable the slit to be closed or otherwise provide a force against the slit **198** from opening further can be utilized in at least some embodiments. In this regard, in an exemplary embodiment, there is a device embedded or otherwise enclosed within the body that provides a compressive force on the surfaces of the slit.

Note further that there are other manners in which the slit can be managed. Instead of or in addition to driving the surfaces of the slit towards each other or providing a force resisting opening of the slit, the slit can be plugged in a manner analogous to utilizing a cork to plug a bottle of wine or the like. In this regard, FIG. **28A** duplicates FIG. **24**, except depicting the plug **195** plugging the slit **198**. As can be seen, the plug **195** is connected to the magnet apparatus **160**. In this regard, the plug can have dual utilitarian value in that it can be utilized to aid in extracting and/or placing the magnet **160** between the plates. That said, in an alternative embodiment, plug **195** can be a separate component to the magnet. It is further noted that in an exemplary embodiment, the plug **195** is configured such that the magnet apparatus **160** can rotate according to the teachings detailed herein without adjusting or otherwise interfering with the location of the plug in the slit **198**.

In view of the above, it can be seen that in an exemplary embodiment, no part of the magnet apparatus **160** forms an outer surface of the implantable component **100**. In this regard, in an exemplary embodiment, this ensures that only the elastomeric material of the body is exposed. In exemplary embodiment, this can have utilitarian value in that less bacterial attachment will occur as bacterial attachment is lower with respect to silicone them with respect to titanium or other materials forming the outer boundary of the magnet apparatus **160**. In an exemplary embodiment, utilitarian biofilm resistance can be achieved through maintaining the

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opposite surfaces of the slit **198** smooth, at the same level (no step), and in close proximity to one another.

FIG. **28B** presents another exemplary embodiment which has a ramp structure **172R**, wherein the ramp structure **172R** is configured to guide the magnet (and thus the magnet apparatus), during removal thereof from the body, towards the slit **198**. In an exemplary embodiment, the ramp structure **172R** is a separate component from the plate **172**. In an exemplary embodiment, the two are linked by additional structure, or otherwise joined together by a suitable mechanical joining system (e.g., welding). Alternatively, the two are simply embedded or otherwise supported within the body as separate components. In an alternative embodiment, the ramp **172R** is a portion of the bottom plate. That is, the bottom plate has a first portion that is configured to be parallel with the upper plate, and a portion that is angled, bent or otherwise canted relative to that first portion.

FIG. **28C** presents a portion of the implantable component **100** according to a slightly alternate exemplary embodiment, with the view thereof generally corresponding to the view of FIG. **24**, except that the coil **137** is located further away from the plates and the slit **198**. In this regard, it can be seen that the body portion extends further away from the plates than in the exemplary embodiment of FIG. **24**, and thus the coil **137** also is located further away from the plates and the slit **198** than an exemplary embodiment of FIG. **24**.

FIG. **29** depicts a top view of an exemplary plug-magnet apparatus combination. In this exemplary embodiment, it can be seen that the plug has a relative diameter that is smaller than the maximum diameter of the magnet apparatus. This can have utilitarian value with respect to slits **198** that have a major axis that is smaller than the maximum diameter of the plug. That said, in an alternate embodiment, the relative diameter can be larger than the maximum diameter of the magnet apparatus or can be the same as the maximum diameter of the magnet apparatus.

Accordingly, in an exemplary embodiment of the embodiments utilizing the slits detailed herein and/or variations thereof, the magnet is part of a magnet apparatus, the magnet apparatus including a first portion (e.g., the plug **195**), wherein the first portion is located in the slit **198**, resisting further closure of the slit, thereby creating a seal between the slit **198** and the first portion **195**. Corollary to this is that in at least some embodiments, the plug **195** is configured to expand the slit, at least slightly, beyond the size of the slit in a relaxed position, thereby establishing the seal. It is further noted that in at least some embodiments, any of the aforementioned features utilized with the slits detailed herein can be utilized to seal the slit **198**. Note that by seal, it is not meant that a hermetic seal is established. That said, in an alternative embodiment, a hermetic seal can be established according to some implementations of the teachings detailed herein, if not with silicone, with some other material (or a composite material can be utilized, where the slit is formed by a material that can form a hermetic seal, and that material is bonded or otherwise attached to the silicone or other material). That said, the slit can be configured to prevent “larger” matter from entering, an/or can establish a seal that is concomitant with any permeability features of the body in general (e.g., the overall body effectively performs as if the body does not have a slit). It is further noted that while the ends of the slits are depicted as tapering towards each other from the respective upper and lower surfaces thereof, in an alternative embodiment, the ends of the slit can encompass a slightly wider circular area so as to relieve stress and/or avoid “tearing” of the elastomeric material of the housing.

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FIGS. **24** and **25** depict the slit **198** being located in a sidewall of the body of the implantable component **100**, as opposed to the top wall or the bottom wall (the walls configured to be located parallel to the skin, and in the case of a cochlear implant, the mastoid bone of the recipient when the medical device is implanted). More generally, the outer dimensions of the body **199** have a length (the direction along the longitudinal axis of the body (the horizontal direction of FIGS. **1B** and **1C**)), a width (the vertical direction of FIG. **1B**), and a height (the thickness/the vertical direction of FIG. **1C**), wherein the height is measured through the magnet, wherein the height is the smallest dimension, and wherein the slit **198** is located between points on the two surfaces establishing the height dimension (e.g., points **24A** and **24B**, as shown in FIG. **24**). Still further, as can be seen from the FIGS., the slit **198** is configured to enable ingress and egress of the magnet **160** in a direction having a major component in a Cartesian coordinate system in at least one of the X or Z direction, wherein the Y direction is normal to a surface of the body configured to lie against a mastoid bone of a recipient of the implantable medical device (the surface of point **24B** of FIG. **24**). In this regard, as can be seen from FIG. **24**, for magnet **160** to be removed, it must extend a greater distance in the X direction (the horizontal of FIG. **24**) than in the Y direction (the vertical of FIG. **24**), and thus the direction of Y is a minor component of the movement of the magnet **160** during ingress and egress (as it is smaller than the X component—the Z component is zero, as the Z component extends out of the page of FIG. **24**, but in an embodiment where the slits **198** is located on the lateral sides of the body (as opposed to the longitudinal side), or in between, the Z component would be non-zero).

Note further that in the embodiment of FIGS. **24** and **25**, the medical device includes an electromagnetic communication coil **137** extending about the magnet **160**. The medical device includes a functional component (stimulator **122**) communicatively linked to the communication coil **137**, the functional component **122** and the slit **198** being located opposite one another relative to the magnet **160**. This is opposed to a scenario where the slit was located at point **24A** or **24B**.

It is noted that embodiments include methods of utilizing the teachings detailed herein and/or variations. In this regard, it is noted that any disclosure of any device or system corresponds to a disclosure of a method of using and a method of making that device and/or system. Further, any disclosure of any method detailed herein also corresponds to a disclosure of a device for executing the method and/or a system for executing the method. In this regard, an exemplary method will now be described, where, as just noted, embodiments include a device configured to execute any or all of the method actions that follow.

Referring now to FIG. **30**, there is an exemplary flowchart **3000**, which corresponds to an exemplary method. Flowchart **3000** includes method action **3010**, which entails subjecting a subcutaneous medical device containing a magnet, such as any of the medical devices detailed herein and/or variations thereof, to a magnetic field of at least 0.2 T, such as that resulting from an MRI machine, thereby imparting a torque onto the magnet, the torque having a component in a plane normal to a surface of skin of the recipient. It is noted that the at least 0.2 Tesla magnetic field is a threshold value. Exemplary embodiments can entail subjecting the magnet to a magnetic field of at least 0.2 T, 0.5 T, 1.0 T, 1.5 T, 2.0 T, 2.5 T, 3 T or 4 T or 7 T or more. It is further noted that with respect to the component of the

torque, this means that if the torque is divided up into planes lying on the Cartesian coordinate system, a component of the torque will lie on the plane that is normal to the skin of the recipient (e.g., of the X and Z axis are located on the tangent surfaces of the skin, the Y axis is normal to the surface of the skin). There may be a component of the torque imparted onto other planes, but there will be at least a torque component located on the aforementioned plane. An exemplary embodiment, this is the major torque component. That is, of all of the torque components, the component lying on this plane will be the largest.

Method **3000** further includes method action **3020**, which entails limiting and/or opposing at least a portion of the torque of the magnet that is imparted to a support apparatus (e.g., the plates) of the medical device supporting the magnet (either directly or indirectly) via structure of the subcutaneous medical device. In an exemplary embodiment, the elimination of all torque that is imparted into the support apparatus can meet this method action, providing that such an arrangement can be manufactured in a utilitarian manner. In an exemplary embodiment, the limitation of the amount of torque that is applied to the magnet that is imparted into the support apparatus can be limited and/or opposed to/by about 35%, 40%, 45%, 50%, 55%, 60%, 65%, 70%, 75%, 80%, 85%, 90%, 95% and/or 100% or an value or range of values in between in about 1% increments of the torque applied to the magnet (e.g., at 50%, half the torque applied to the magnet is imparted into the support apparatus, at 10%, only  $\frac{1}{10}^{th}$  of the torque applied to the magnet is imparted into the support apparatus, etc.).

In an exemplary embodiment, the action of limiting at least a portion of the torque of the magnet that is imparted to support apparatus of the medical device entails permitting the magnet to rotate at least about 5° in the plane relative to a position of the magnet in the absence of the external magnetic field. In an exemplary embodiment, this entails permitting the magnet to rotate at least about 10°, 15°, 20°, 25°, and/or about 30°, or more, or any value or range of values therebetween in about 1° increments. Still further, in an alternate embodiment, this entails preventing the magnet from rotating any more than at least about 5°, about 10°, about 15°, about 20°, about 25°, and/or about 30°, and/or about 35° or any value or range of values therebetween in about 1° increments.

In an exemplary embodiment, the action of limiting at least a portion of the torque of the magnet that is imparted to the support apparatus of the medical device entails permitting the magnet to slide relative to the support apparatus such that the support apparatus expands from a contracted state (e.g., the plates **170** and **172** move away from one another), thereby transferring energy from the torque into a body of the implanted medical device (e.g., the body made from elastomeric material **199** as detailed above) which transferred energy is absorbed by the body. This as opposed to a scenario where the torque is transferred into the body, and the body transfers the torque into the tissue of the recipient, where the energy transferred into the tissue is absorbed by the tissue. That said, it is noted that owing to the expansion of the support structure, and thus the expansion of the body, a force will be imparted onto the tissue of the recipient. However, the energy absorbed by the body of the implanted medical device can be more than the energy transferred to the skin of the recipient as a result of the torque. In an exemplary embodiment, over 50% of the energy that is transferred from the magnet is absorbed by the body of the implanted device, and thus less than 50% of the energy that is transferred from the magnet is available to be

absorbed by the tissue/skin of the recipient. In an exemplary embodiment, over about 55%, 60%, 65%, 70%, 75%, 80%, 85%, 90%, 95%, or more of the energy that is transferred from and/or into the magnet is absorbed by the body of the implanted device.

In an exemplary embodiment, the magnet is permitted to partially rotate so that the poles of the magnet are more aligned with the external magnetic field, while not necessarily being completely aligned, so as to reduce the torque on the implant resulting from the interaction of the external magnetic field with the magnetic field of the permanent magnet, relative to that which would be the case if the magnet was restrained from rotating relative to the body of the implant. The amount of rotation that is permitted is within the boundaries of the design of the implant so as to substantially ensure that upon the removal of the external magnetic field, the magnet returns to its at rest position, and the implant is not permanently damaged.

Corollary to the above, it is noted that in an exemplary embodiment, method **3000** further includes limiting at least a portion of the torque of the magnet that is imparted into tissue of the recipient of the medical device via structure of the subcutaneous medical device. In an exemplary embodiment, about 50%, 55%, 60%, 65%, 70%, 75%, 80%, 85%, 90%, 95%, or more of the energy that is transferred into the magnet is prevented from being transferred to tissue of the recipient. Thus, as will be understood from the aforementioned examples, in at least some embodiments, the methods according to the teachings detailed herein include limiting effectively all of the torque of the magnet that is imparted into tissue of the recipient of the medical device via structure of the subcutaneous medical device.

It is further noted that in at least some of these exemplary methods, the magnet is restrained from rotating more than a quarter revolution (90°) relative to the position of the magnet and the absence of the magnetic field, and in some embodiments the magnet is restrained from rotating more than an eighth of a revolution (45°) relative to the position of the magnet absence of the magnetic field. Still further, in some embodiments the magnet is restrained from rotating more than about 10°, 15°, 20°, 25°, 30°, 35°, or 40° relative to the position of the magnet absence of the magnetic field.

In view of the above, in at least some exemplary embodiments, implantable component is configured such that the plates generally remain parallel to one another as the magnet apparatus rotates when exposed to the magnetic field(s) having the strengths detailed herein, at least with respect to some of those magnetic fields. In an exemplary embodiment, the plates remain parallel to one another over one or more or all or any of the aforementioned rotational angles detailed herein of the magnet apparatus. In an exemplary embodiment, the plates remain parallel to one another over one or more or all or any of the aforementioned separation distances (D1 to D2) and/or changes in the separation distances (D2-D1) detailed herein.

In at least some exemplary embodiments, the implantable component is configured to convert the rotational motion of the magnet apparatus to the translational movement of the plates detailed herein. In an exemplary embodiment, the implantable component is configured to disperse or otherwise diffuse the energy across a greater area of the resilient material of the body than that which would be the case if the rotation of the magnet apparatus was directly resisted by the elastomeric body (e.g., in a scenario where the magnet support structure rotated in a one-to-one relationship with the magnet (with respect to at least one plane of rotation).) That is, by way of example only and not by way of

limitation, a comparison between the teachings detailed herein can be made to a scenario where the plates **170** and **172** are rigidly attached to the magnet apparatus/magnet such that any rotation of the magnet also corresponds to an equal rotation of the plates, at least with respect to at least one of plane of rotation. In this regard, in exemplary embodiments, instead of transferring the torque imparted onto the plates by way of the rotation of the magnet (which causes rotation of the plates by an amount that is limited by the resistance to the rotation of the plates by the body), as would be the case in the aforementioned control scenario, the torque is converted into a linear movement of the plates away from one another, where the energy of the torque is dissipated into the elastomeric body via the stretching of the elastomeric body in a linear direction.

In an exemplary embodiment, the teachings detailed herein and/or variations thereof avoid localized loading, or at least reduce the localized, which can occur with a structure having the same outer dimensions as the plates (albeit when rigidly connected to the magnet apparatus/magnet, at least such that any rotation of the magnet results in rotation of the plates at least in one plane of rotation)—the control structure. In this regard, in this exemplary control scenario where the plates are rigidly linked to the magnet apparatus, the energy/force resisting rotation of the magnet apparatus (and thus the plates) is concentrated at the edges of the plates. (The adjacent parts of the elastomeric body remained relatively unloaded relative to the portions of the elastomeric body near the upper/lower edges of the plates.) Conversely, because in at least some exemplary embodiments, the plates do not rotate, or at least rotate less than they would in the aforementioned scenario where the plates are rigidly attached to the magnet apparatus, the energy/force resisting movement of the plates is diffused over a larger area of the plates (or at least any concentrations of energy are located further away from the edges of the plates or otherwise located over a greater area). (The adjacent parts of the elastomeric body relative to the portions of the elastomeric body near the upper/lower edges of the plates are more loaded as compared to the aforementioned example.)

FIG. **31** presents an exemplary tool usable in an exemplary embodiment to remove and/or install exemplary magnet apparatuses in an exemplary embodiment. FIG. **31** depicts a tool **3100**, which includes a handle **3110**, and a hook **3120** extending therefrom. In an exemplary embodiment, the hook **3120** is sized and dimensioned to fit between the slit noted above and extend therethrough through the path to reach the magnet apparatus located between the aforementioned plates/to push the magnet down the path to the location between the aforementioned plates. Corollary to this is that FIG. **32** depicts an exemplary magnet apparatus **16032**, including a handle **3211** sized and dimensioned to receive the hook of the tool **3100**, as is depicted by way of example only and not by way of limitation in FIG. **33**. In at least some embodiments, as noted above, the tool **3100** can be used to push the magnet **16032** through the path to the location between the plates. FIG. **34** depicts an alternate embodiment of a magnet apparatus **16034**, where the magnet apparatus includes a rectangular plate magnet instead of a circular magnet simply in the interests of conveying the fact that a wide arrangement of magnets and magnet apparatuses can be utilized in at least some embodiments. As can be seen, the apparatus **16034** includes a looped path **3411** in the magnet that is sized and dimensioned to receive the hook of the tool **3100**. While the openings of the looped path **3411**, and the looped path in general, is depicted lying in the plane of FIG. **34**, in an alternate embodiment, the path can

extend through the plane of FIG. **34** (e.g., into the page). Any arrangement of a handle device that can enable the teachings detailed herein and/or variations thereof to be practice can be utilized at least some exemplary embodiments.

FIG. **35** presents an exemplary scenario of utilizing the tool **3100** to position and/or remove the magnet **160**. As can be seen, the hook **3120** extends through the path leading from the slit to the magnet **160**. Also as can be seen, the elastomeric material of the body **198** can be seen to be deformed at the location proximate the upper plate **170** by the hook **3120**, thus giving an example of how the elastomeric material of the body can accommodate the insertion and/or removal process of the magnet.

It is noted that any method detailed herein also corresponds to a disclosure of a device and/or system configured to execute one or more or all of the method actions detailed herein. It is further noted that any disclosure of a device and/or system detailed herein corresponds to a method of making and/or using that the device and/or system, including a method of using that device according to the functionality detailed herein.

It is further noted that any disclosure of a device and/or system detailed herein also corresponds to a disclosure of otherwise providing that device and/or system.

It is noted that in at least some exemplary embodiments, any feature disclosed herein can be utilized in combination with any other feature disclosed herein unless otherwise specified. Accordingly, exemplary embodiments include a medical device including one or more or all of the teachings detailed herein, in any combination.

Note that exemplary embodiments include components detailed herein and in the figures that are rotationally symmetric about an axis thereof (e.g., the magnet apparatus **160**, the plates, etc.). Accordingly, any disclosure herein corresponds to a disclosure in an alternate embodiment of a rotationally symmetric component about an axis thereof. Moreover, the exemplary embodiments include components detailed in the figures that have cross-sections that are constant in and out of the plane of the figure. Thus, the magnet apparatus **160** can correspond to a bar or box magnet apparatus, etc.).

While various embodiments of the present invention have been described above, it should be understood that they have been presented by way of example only, and not limitation. It will be apparent to persons skilled in the relevant art that various changes in form and detail can be made therein without departing from the spirit and scope of the invention.

What is claimed is:

1. A method, comprising:

subjecting a subcutaneous medical device containing a magnet to a magnetic field produced by a magnetic resonance imaging (MRI) machine, thereby imparting a torque onto the magnet, the torque having a component in a first plane normal to a surface of skin of a recipient of the subcutaneous medical device, wherein the magnet is contained in a hermetically sealed container; and

rotating the magnet within the container in the first plane a first limited amount owing to the magnetic field, the limited amount being limited by the container.

2. The method of claim 1, wherein:

the first limited amount is limited by contact of the magnet with an interior of the container.

3. The method of claim 1, wherein:

the magnet has its north-south poles on lateral sides of the magnet.

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4. The method of claim 1, further comprising:  
rotating the magnet in a second plane normal to the first  
plane also owing to the magnetic field.
5. The method of claim 1, further comprising:  
rotating the magnet in a second plane also owing to the  
magnetic field, wherein the second plane is normal to  
a longitudinal axis of the magnet.
6. The method of claim 1, further comprising:  
rotating the magnet in a second plane also owing to the  
magnetic field, wherein the second plane moves rela-  
tive to the first plane owing to rotation of the magnet in  
the first plane.
7. The method of claim 1, wherein:  
the action of rotating the magnet in the first plane limits  
at least a portion of the torque of the magnet that is  
imparted to the subcutaneous medical device.
8. An implantable medical device, comprising:  
a magnet apparatus including a magnet and a container  
housing the magnet; and  
a body encompassing the magnet apparatus, wherein  
the implantable medical device is configured to enable  
rotation of the magnet in the container relative to the  
container in at least two planes normal to each other,  
and  
the magnet has a longitudinal axis that extends towards a  
top of the container and that extends towards a bottom  
of the container.
9. The apparatus of claim 8, wherein:  
the magnet is polarized to have north-south poles posi-  
tioned more laterally than longitudinally.
10. The apparatus of claim 8, further comprising:  
a lubricant in the container that reduces friction between  
the magnet and an inner surface of the container.
11. The apparatus of claim 8, wherein:  
the implantable medical device is a hearing prosthesis.
12. The apparatus of claim 8, wherein:  
rotation of the magnet in at least one of the at least two  
planes is limited by interior walls of the container  
housing the magnet.
13. The apparatus of claim 12, wherein:  
the limited rotation is due to contact of lateral portions of  
the magnet with portions of interior walls of the con-  
tainer.
14. The apparatus of claim 8, wherein:  
a first plane of the at least two planes is normal to a  
longitudinal axis of an interior of the container; and  
a second plane of the at least two planes is normal to the  
first plane.
15. An implantable medical device, comprising:  
a magnet apparatus including a magnet and a container  
housing the magnet; and  
a body encompassing the magnet apparatus, wherein  
the magnet has a longitudinal axis,  
the implantable medical device is configured to enable  
rotation of the magnet relative to the container about an  
axis normal to the longitudinal axis, and  
the magnet apparatus has a curved profile located on a  
plane normal to the longitudinal axis.
16. The implantable medical device of claim 15, wherein:  
the magnet has a cross-section lying on a plane normal to  
the longitudinal axis; and  
the cross-section is a majority circular.
17. The implantable medical device of claim 16, wherein:  
the implantable medical device is also configured to  
enable rotation of the magnet relative to the container  
about the longitudinal axis.

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18. The implantable medical device of claim 15, wherein:  
the magnet is polarized to have north-south poles posi-  
tioned closer to a plane normal to the longitudinal axis  
than to a plane lying on the longitudinal axis.
19. The implantable medical device of claim 15, wherein:  
with respect to a cross-section of the magnet lying on a  
plane lying on the longitudinal axis, the cross-section  
of the magnet has a curved portion.
20. The implantable medical device of claim 19, wherein:  
the curved portion arcs away from a sidewall of an interior  
of the container, the sidewall extending normal to a  
longitudinal axis of an interior of the container.
21. The implantable medical device of claim 15, wherein:  
with respect to a cross-section of the magnet lying on a  
plane lying on the longitudinal axis, the cross-section  
of the magnet has a curved portion; and  
the curved portion enables a greater rotation about the  
axis normal to the longitudinal axis relative to that  
which would be the case in the absence of the curved  
portion.
22. An implantable medical device, comprising:  
a silicone body;  
a magnet; and  
an inductance coil extending about the magnet, the induc-  
tance coil being supported by the silicone body,  
wherein  
the implantable medical device is configured to enable the  
magnet to rock about a lateral axis of the magnet  
relative to the inductance coil extending about the  
magnet and relative to the silicone body when the  
implantable medical device is exposed to an external  
magnetic field of a magnetic resonance imaging (MRI)  
machine.
23. The implantable medical device of claim 22, wherein:  
the magnet has an outer shape that enables the magnet to  
rock relative to a structure of the implantable medical  
device that is separate from the coil and separate from  
the silicone body encompassing the magnet and the  
structure;  
the magnet has a longitudinal axis; and  
the longitudinal axis extends through the structure.
24. The implantable medical device of claim 23, wherein:  
the structure is in contact with the coil.
25. The implantable medical device 24, wherein:  
the structure is in direct contact with the magnet.
26. The implantable medical device of claim 24, wherein:  
the magnet is coated with a biocompatible material.
27. The implantable medical device of claim 23, wherein:  
the structure is interposed between a portion of the body  
and the magnet.
28. The implantable medical device of claim 23, wherein:  
the structure includes a flat surface in direct contact with  
the body, wherein the flat surface is bounded by a  
circle, wherein the flat surface faces away from the  
magnet.
29. The implantable medical device of claim 23, wherein:  
the longitudinal axis rocks relative to the structure when  
the magnet rocks;  
the structure is interposed between a portion of the body  
and the magnet; and  
when the implantable medical device is implanted in a  
recipient above a skull of the recipient, the longitudinal  
axis extends through the skull.
30. The implantable medical device of claim 23, wherein:  
the implantable medical device is also configured to  
enable the magnet to rotate about the longitudinal axis  
of the magnet.