

# First RoboSoft Plenary Meeting

March 31 – April 1, 2014

Scuola Superiore Sant'Anna, Pisa, Italy



Scuola Superiore  
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## A physical model of the human larynx and a biorobotic prototype of vocal cords

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# RESEARCH OBJECTIVES

The BioRobotics Institute, Scuola Superiore Sant'Anna, Pisa, Italy  
Prof.ssa Laschi and Dott.Cianchetti

Cisanello Hospital, University of Pisa  
Prof. Ursino

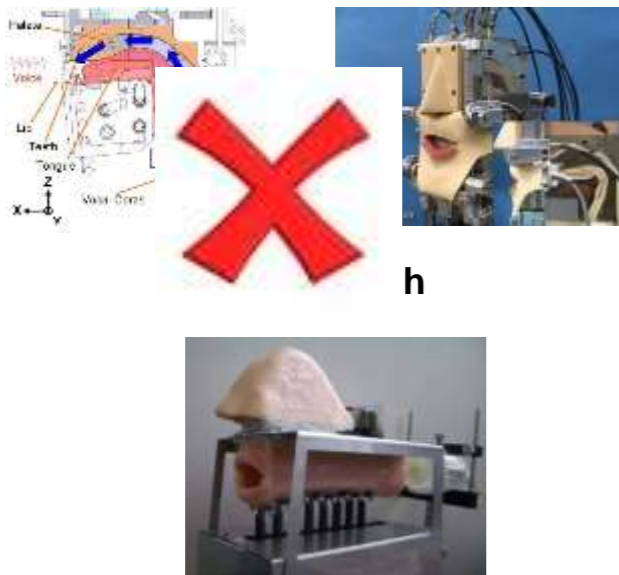


Development of a biorobotic platform of the human larynx that replicates its **main components** and **functions**. It will be able to improve the knowledge on human larynx physiology as a preliminary step for the development of new diagnostic, therapeutic and rehabilitative devices.

## STATE OF THE ART

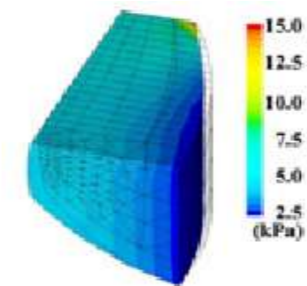
### ROBOTIC LARYNX

#### Waseda Talker WT-7R2

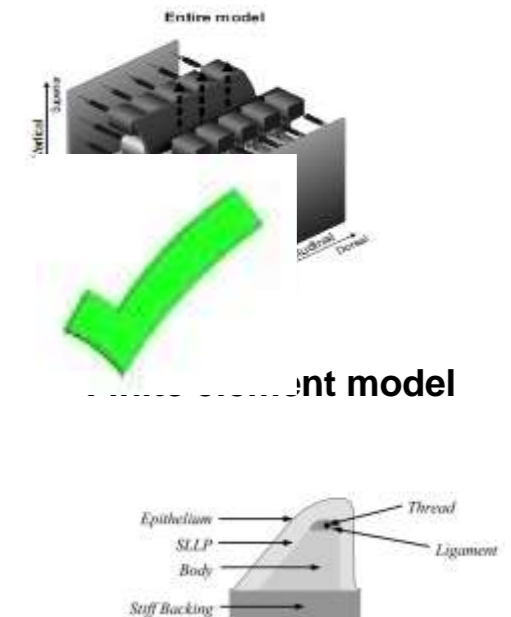


### THEORETICAL AND EXPERIMENTAL MODELS

#### Mass – Spring model



#### Synthetic model



### SYNTHETIC MULTILAYER SELF-OSCILLATING MODELS

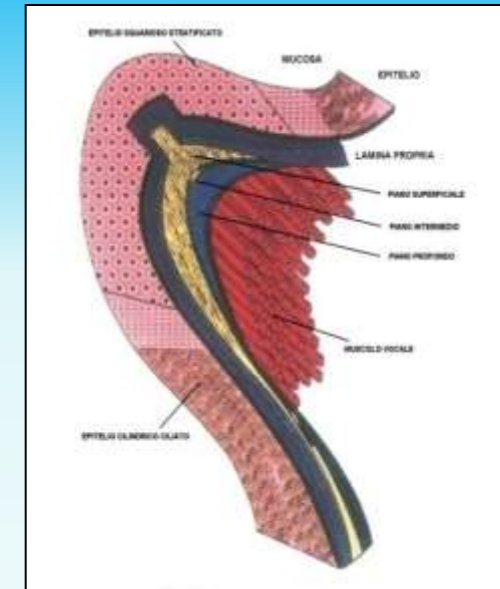
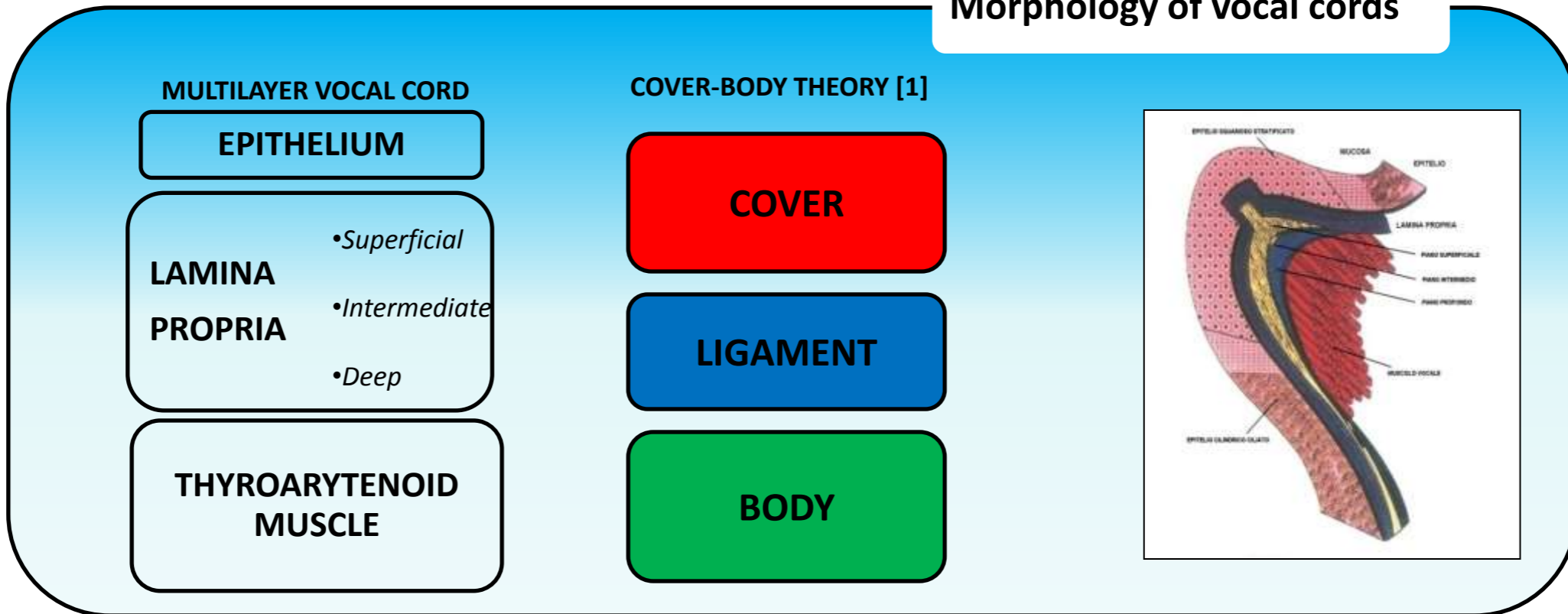
**Direct control** on the characteristics of the platform  
(shapes, position, dimension and mechanical properties)

The combination between **morphology** and **mechanical properties** defines the vocal fold oscillation



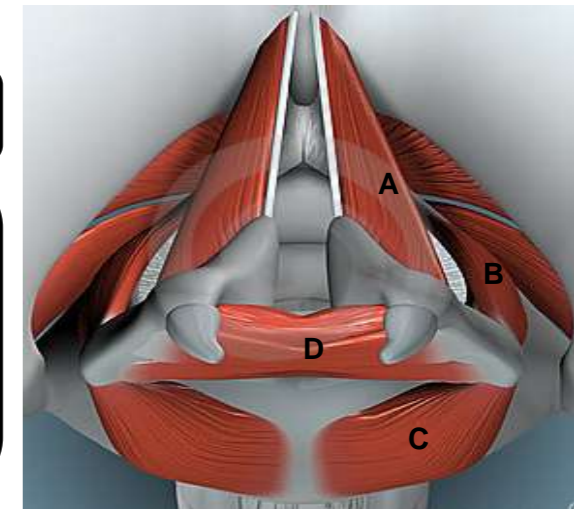
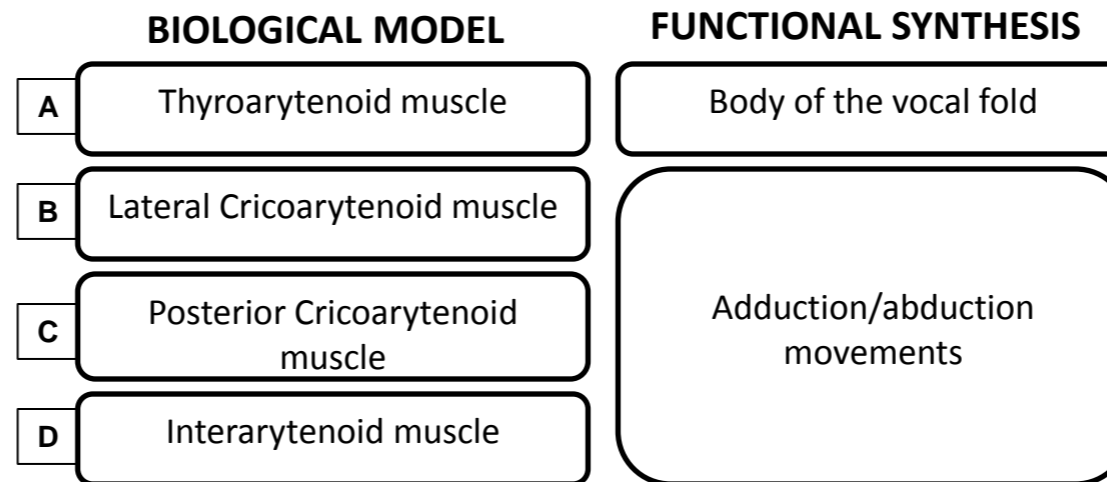
## ANATOMY OF HUMAN LARYNX

### Morphology of vocal cords



### Functional synthesis

The robotic simulator of the human larynx has to catch the key principles and the key components of the natural counterpart.



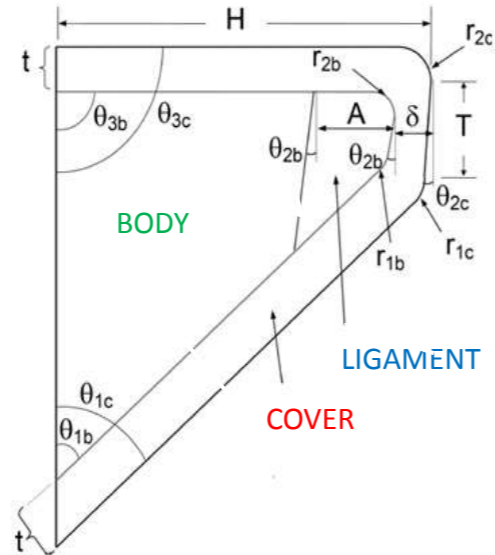
[1] M. Hirano, Y. Kakita, *Cover-body theory of vocal fold vibration*, *Speech Science: Recent Advances*, 1985, pp. 1-46.



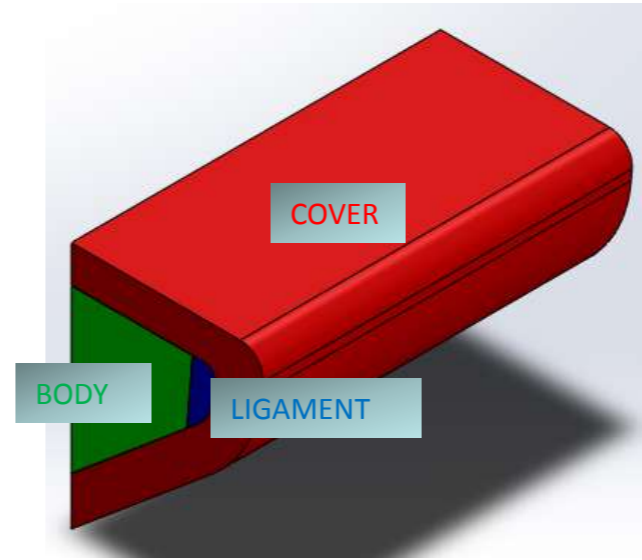
## PROTOTYPE DEVELOPMENT

### MULTILAYER VOCAL CORDS

Soft materials have been used to fabricate the prototype vocal cords with a multi phase casting procedure. **Silicone** has been chosen for its capability in recreating behavior close to the natural tissue



Vocal cord model geometry [2]

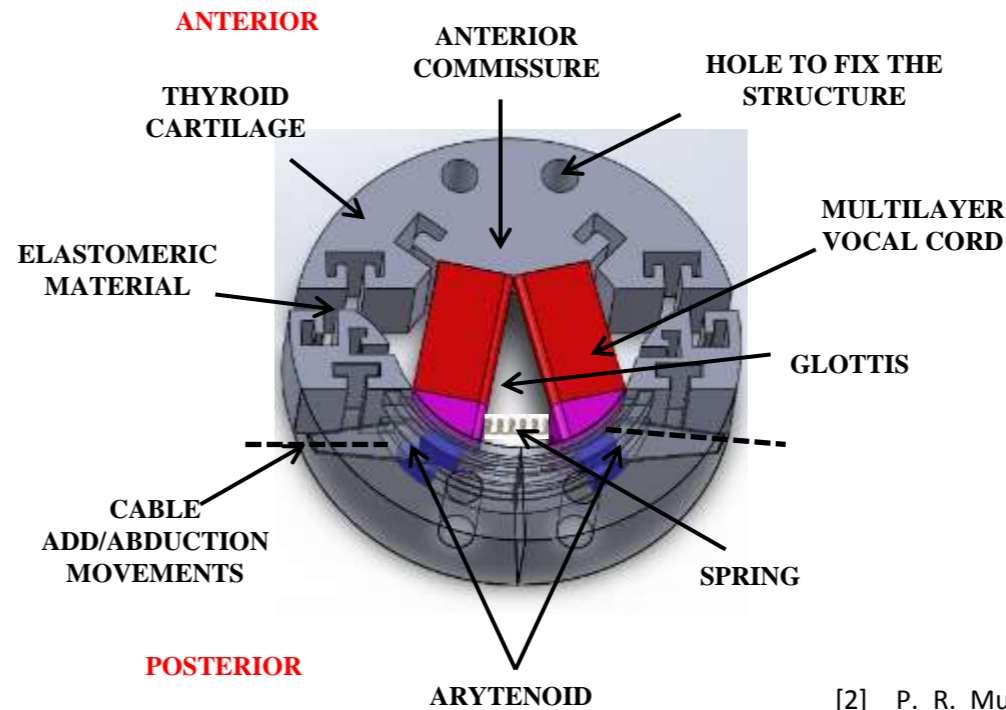


CAD Model

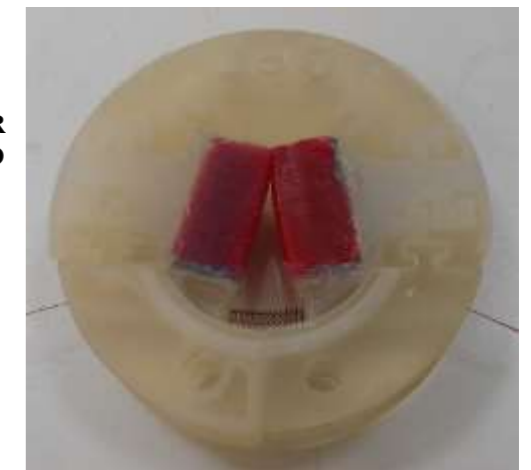


Physical Model

### CAD model of human larynx

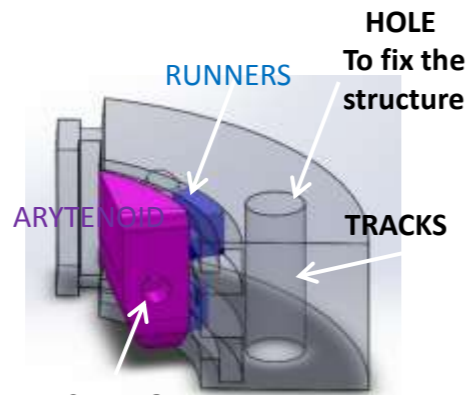


### Physical model of human larynx



### ABD/ADDUCTION MECHANISM

Main components reconstructed using a rapid prototype machine which allows a fast and precise fabrication of very complex parts



CAD Model



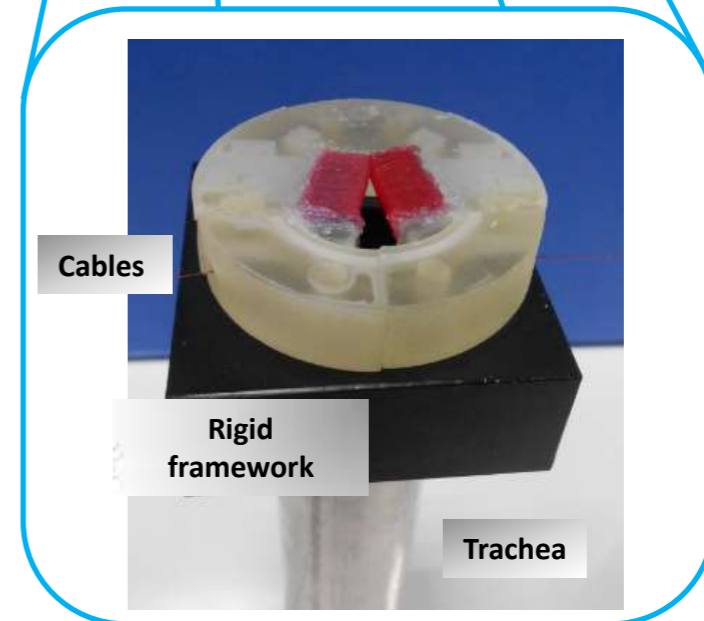
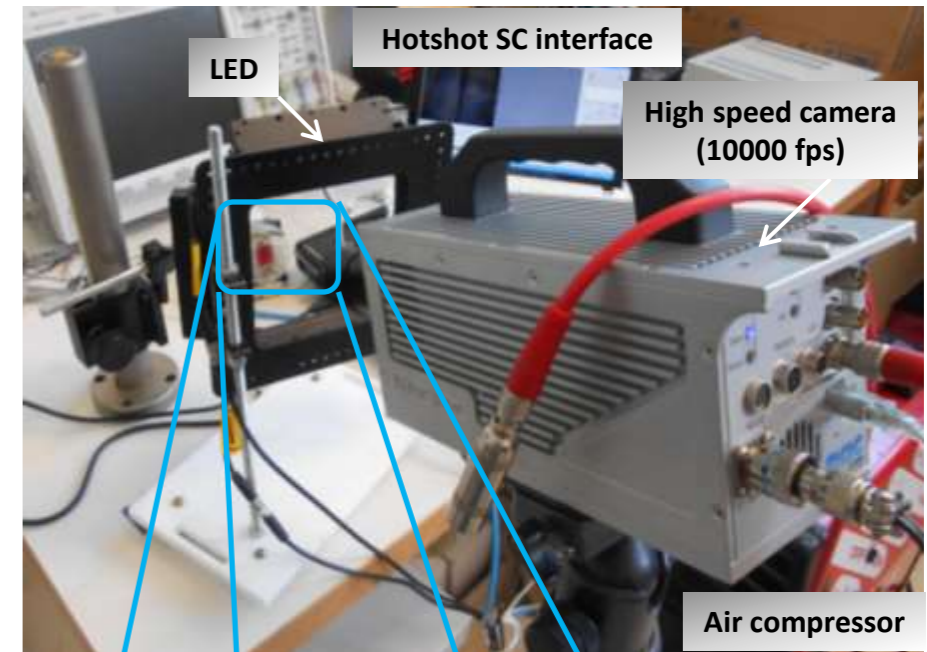
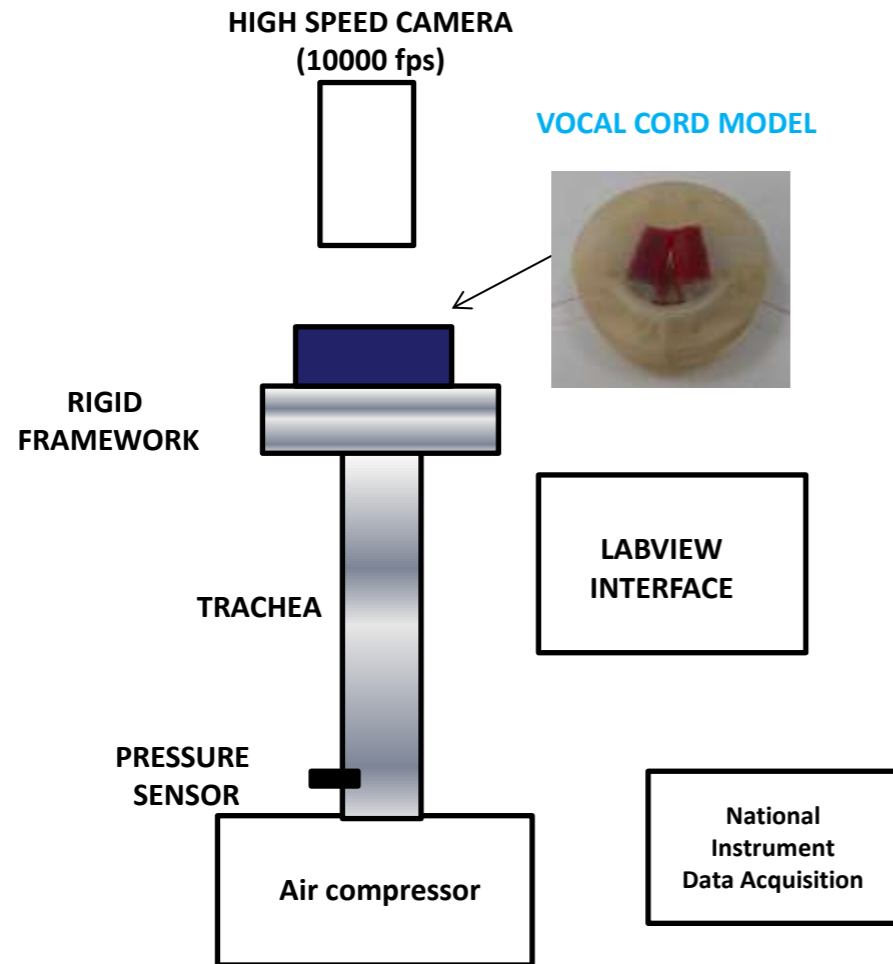
3D printer

[2] P. R. Murray, S. L. Thomson, *Synthetic, multi-layer, self-oscillating vocal fold model fabrication*, J. Vis. Ex, 2011, p. 58,e3498



# EXPERIMENTAL SET UP

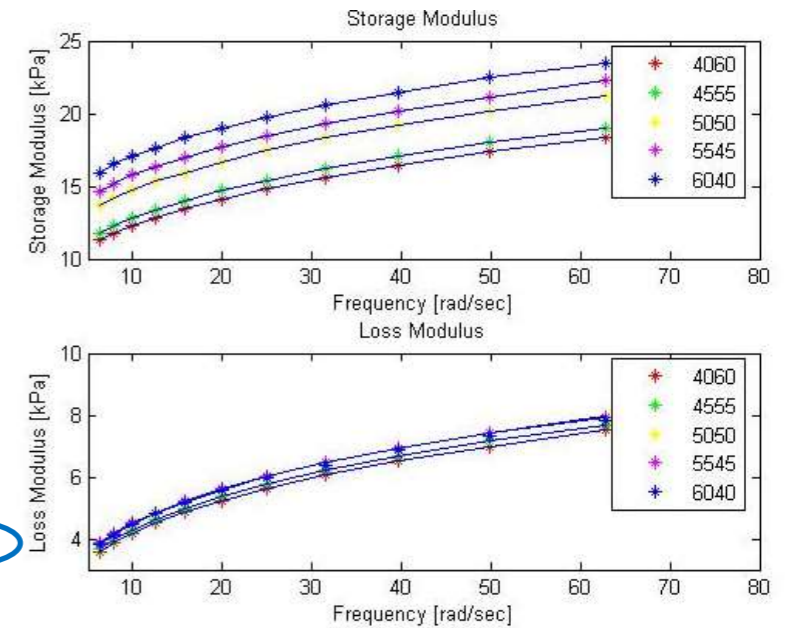
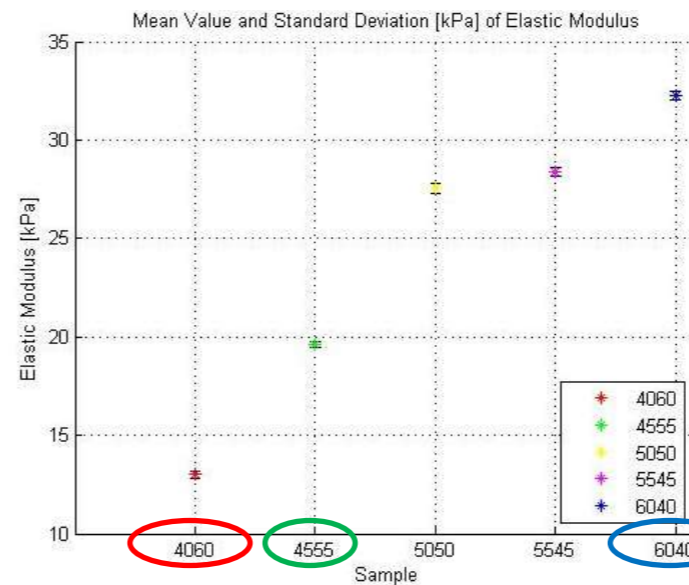
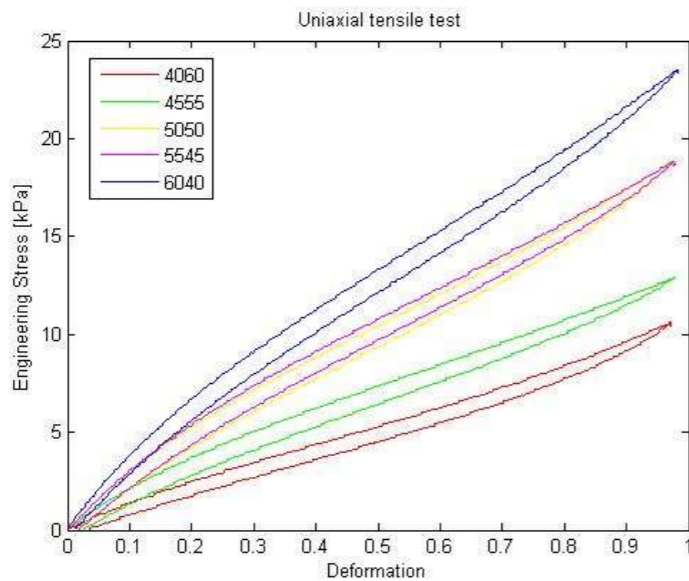
Measurements were performed with the physical model in an experimental platform comprising a controlled air flow and a high-speed camera for measuring vocal cord vibrations. Data included **subglottal pressure, glottal width and oscillation frequency**.



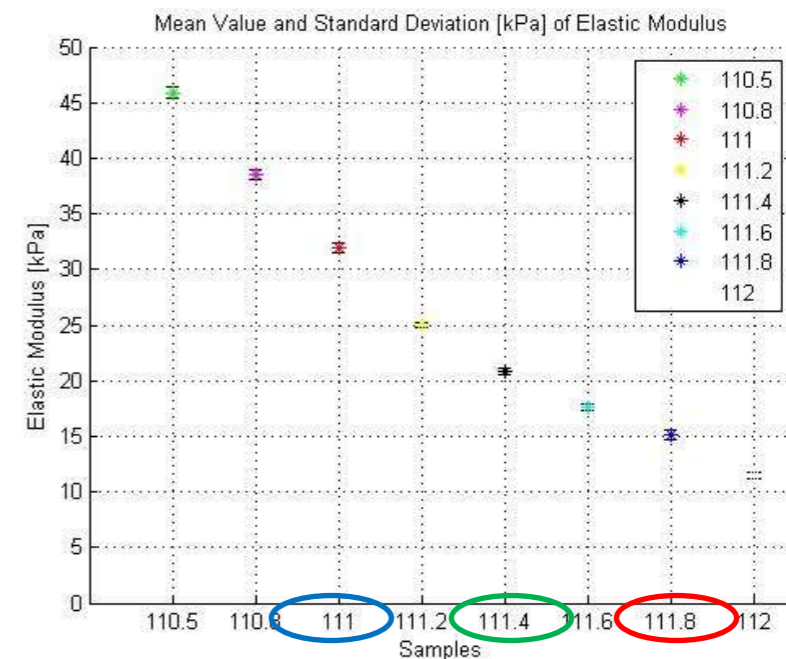
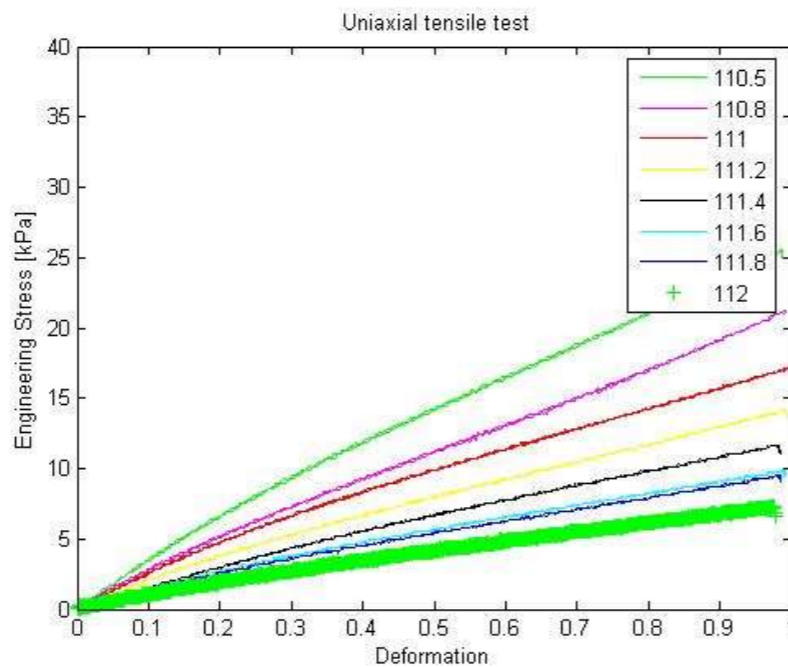
# RESULTS (I)

**MECHANICAL PROPERTIES:** uniaxial tensile test and shear test have been performed to identify soft materials with elastic and rheological properties, as similar as possible, to the natural tissue.

**ECOFLEX 0010**  
(Smooth-On Inc.)



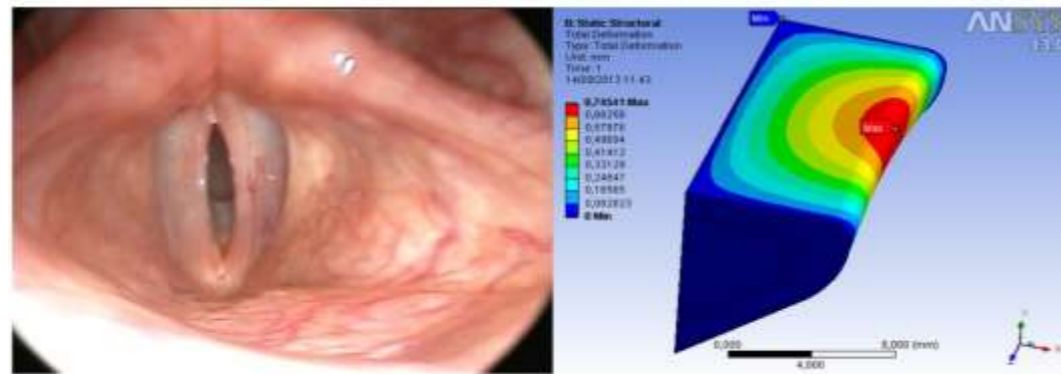
**ECOFLEX 0030**  
+  
**SILICONE THINNER**  
(Smooth-On Inc.)



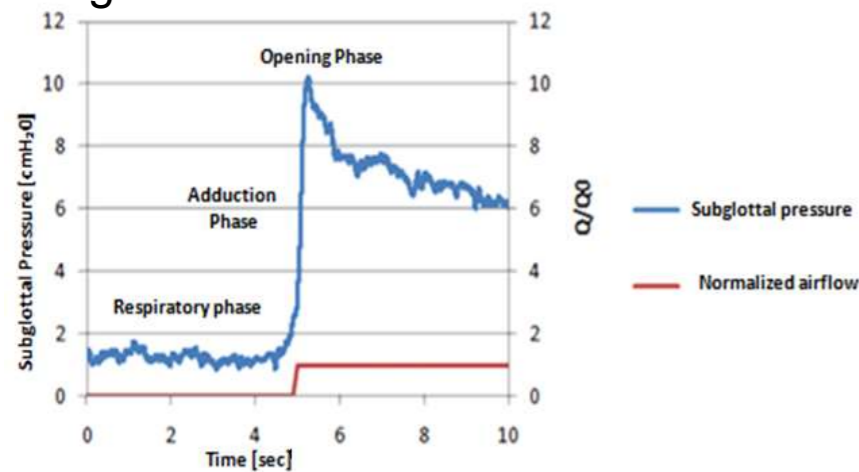
# RESULTS (II)

## FLUID – STRUCTURE INTERACTION

A FEM model (in Ansys®) to simulate the fluid-structure interaction between the airflow and the vocal cord.

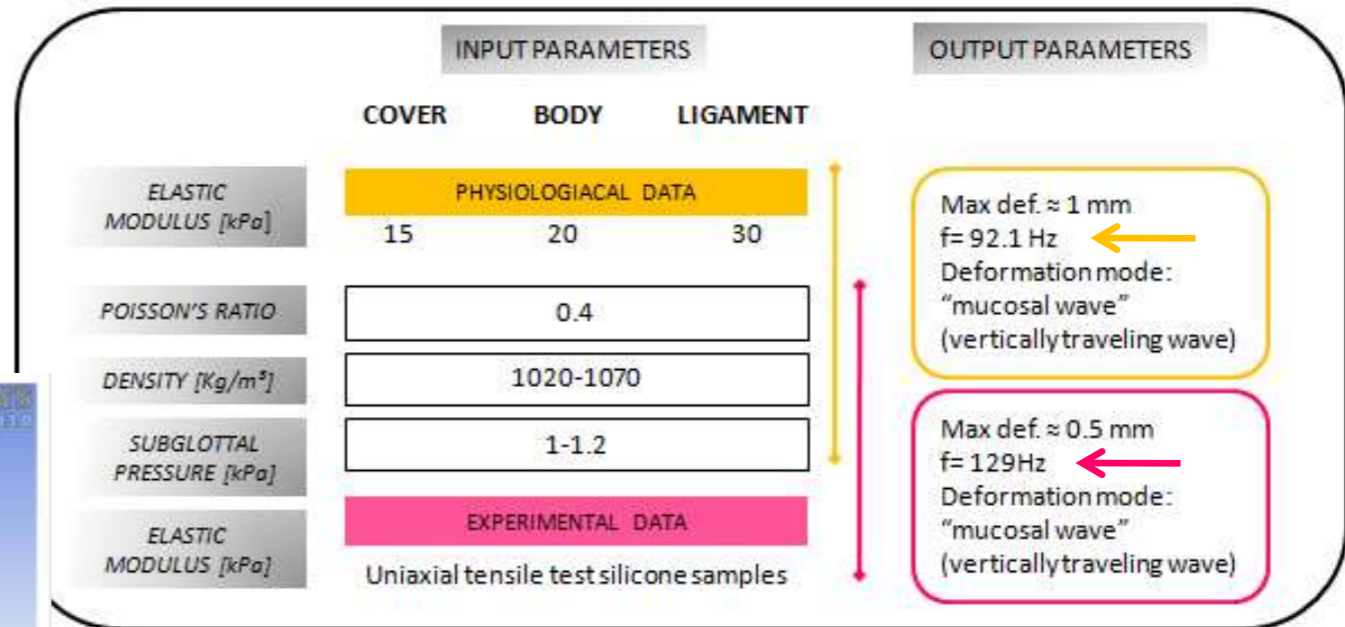


**SUBGLOTTAL PRESSURE:** is high enough to overcome the elastic adhesion force of the vocal cords and separate them causing an increase in the glottal width



**P= 10 cmH<sub>2</sub>O**

Physiologic range: 7-10 cmH<sub>2</sub>O



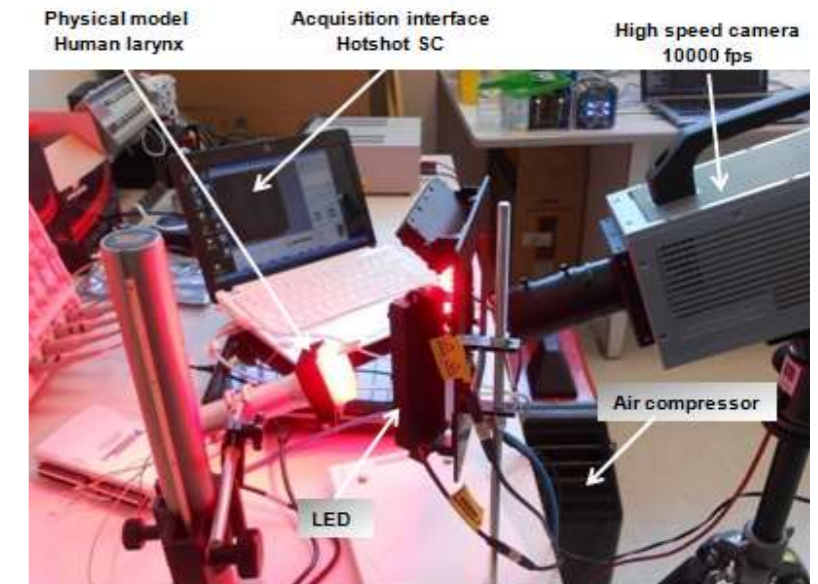
**FREQUENCY:** evaluated experimentally through a video analysis in order to identify the number of oscillation in the time unit.

Test	N° frame	Frequency [Hz]
1	33	151,5
2	30	166,7
3	32	156,25
4	33	151,5
5	31	161,3
6	36	139

$$T = \frac{\Delta frames}{500 (fps)} * \frac{1}{N (oscillations)}$$

**f= 154 Hz**

Physiologic range: 97-250 Hz



## CONCLUSIONS

The experimental results guarantee the feasibility of the biorobotic platform. The physical model of the human larynx will be a fundamental instrument on clinicians hands both for the study of the disease and educational purpose.

### Future works:

- Robotic technologies to actively change the characteristics of the platform (namely shapes and mechanical properties)
- Study of pathological conditions
- Clinical validation





**Thank you for the attention!**

