

Int Poster J Dent Oral Med 2002, Vol 4 No 1, Poster 110

Computer assisted insertion of dental implants

Language: English

Authors: Jakob Brief¹, Stefan Haßfeld¹, U. Sonnenfeld², N. Persky², Robert Krempien³, Martina Treiber³, Joachim Mühling¹ ¹Department of Oral and Maxillofacial Surgery, University of Heidelberg, D-69120 Heidelberg, Germany ²DenX, Moshav Ora 106, Jerusalem 90880, Israel

IP

³Department of Radiology, University of Heidelberg, D-69120 Heidelberg, Germany

International Poster Journal

Date/Event/Venue:

09.06.01 - 10.06.01

2. Assistentenkongreß in der ZMK und an der 2. Jahrestagung des Arbeitskreises für Angewandte Informatik in der DGZMK Berlin, Germany

Introduction

We are introducing a method that combines a pre-operative 3D plan for inserting dental implants with a dental navigation system. The method is based on the visualization of the CT data of the patient's maxilla and mandible. The position and orientation of each implant is clinically planned using the CT data set as well as the size and type of the implant.

The treatment plan supplies the location of the implants in the patient's coordinates and is transferred to the patient using a dental navigation system (DenX's, IGI System).

The system "assists" the dentist during the pre-operative planning and also during the intra-operative procedure, while the optimal treatment plan is applied directly to the patient. A PC based software, IGI allows for simulation, visualization, and planning the surgical intervention.

The system was tested in Israel at the company site as a prototype and will be installed at the University Hospital of Heidelberg for further evaluation and experience until it will be used for clinical application during the middle of 2002.

Material and Method

For evaluation, we used the prototype planning and navigation - System called IGI (DenX, Israel), which tracks the actual position of the handpiece in real-time. The type, size, position and orientation of the implants are planned based on CT data with IGI Software from DenX Ltd.

KaVOTM phantom jaws were used for the tests. Different methods of fiducial locations were used for the different kinds of jaw models. For the EWL surgery model an acrylic splint was prepared and eleven Ceramic spheres, 3 mm in diameter were cemented to the splint's occlusal surface. For the implant model, the above-mentioned spheres were cemented to the jaw itself. The jaws were CT scanned with the artificial landmarks and the digital data were transferred onto the IGI station. The 3D planning of the implantation and the drilling was then performed in the following order:

Virtual implants of 3.75 mm diameter, 10 mm length were used for the tests. 38 drill holes were prepared in 2 model implant jaws, 23 in one jaw and 15 in the other, located at distances of about 5 - 10 mm between the centers of each implant and vertical to the occlusion plane as was determined in the CT scan. Eight more implant sockets were prepared in two surgery model jaws, four on each jaw, drilled in the missing teeth area vertical to the occlusion plane as was determined in the occlusion plane as was determined in the occlusion plane as was determined in the missing teeth area vertical to the occlusion plane as was determined in the CT scan.

It is necessary to brace the patient's maxilla and mandible during treatment so that the patient remains in a fixed position during surgery. The position of the patient was referenced by registering the landmarks. The spheres on the splint and on the jaw implant are used as landmarks for the registration procedure. All the pre-operative determined implant sites were drilled carefully while the IGI system's visual and audio indicators made sure that during the entire procedure there was no deviation from the original plan. The jaws were sent to post operative CT. The digital postoperative CT data were transferred to the IGI station and the saved virtual implants are fused to the CT data using the fiducial location.

In the postoperative CT, the drill holes could be easily seen and defined. The drill hole center top position and end position were defined with the software ruler tool and the 3D coordinates of the top and end center were registered. The same procedure was done with the virtual implants and the deviation between the virtual implant and actual hole was calculated.



 $\ensuremath{\mathsf{IGI}}$ dental planning and navigation system for the positioning of implants / simulation



Controlling the plan while drilling



Executing the drilling, tracking the exact position of the handpiece and the patient (in fixed position).



Implant deviation

deviation of implant top (bone entrance) position in edentulous phantom jaw



deviation of implant end (apex) positions in edentulous phantom jaws

We tested 38 implants within edentulous phantom jaws and 8 implants in partially edentulous phantom jaws (Table 1a-b). We found an accuracy that has a deviation of 0 mm at best and a deviation of 1,2 mm at worst. For both the edentulous and the partially edentulous it is shown that 95% of the deviations are below 1 mm, which coincides with the achievement of the 1 mm accuracy.

Conclusion

The IGI system will offer the dentist an easy to handle tool, which accurately transfers the preoperatively defined implant position directly to the patient during the surgical procedure. While evaluating the systems benefits and precision in a phantom study, we found the system's total accuracy equals 1.0 mm.

Acknowledgement

This research was performed by members of the Department of Oral and Maxillofacial Surgery, Prof. Dr. J. Muehling, University of Heidelberg, at DenX, Moshav Ora 106, Jerusalem 90880, Israel.

The work is being funded partially by the Sonderforschungsbereich 414 "Information Technology in Medicine - Computer and Sensor Supported Surgery" of the Deutsche Forschungsgemeinschaft.

This poster was submitted by Dr. Jakob Brief.

Correspondence address: *Dr. Jakob Brief* Department of Oral and Maxillofacial Surgery, University of Heidelberg INF 400 D-69120 Heidelberg Germany

Poster Faksimile:

Computer assisted insertion of dental implants

J. Brief *, S. Hassfeld *, U. Sonnenfeld **, N. Persky **, R. Krempien +, M. Treiher +, J. Mühling *

Bepartment of Oral and Macillofacial Surgery, University of Heidelberg D-69120 Heidelberg, Germany, Email: Heidelbergde

* * DenX, Moshav Dra 106, Jonualem 90880, Israel

- Department of Radiology, University of Heidelberg, D-69120 Heidelberg, Oermany

Introduction We are introduction a method that combines a pre-operative 3D plan for inserting dettell implicits with detail anxignition system. The method is based on the visualization of the CT data of the patient's anazolla and mandiller. The position and orientation of each implant is denicably gluomed using the CT data set as well as the size and type of the implant. The treatment plan supplies the location of the implants in the petient's occerlines and its transferred to the patient using a dental naivaginous system. (Not:N, NOT System). The system "masses" the dentist during the pre-operative planning and also during the intra-operative proceedure, while the optimal treatment plan is applied thereby to the prismit. A PC based software, ROT allows for simulation, visualization, and planning the surgical intervention.

intervention. The system was tested in Land at the company site as a prototype and will be isoadfed at the University (Euspite) of Heidelberg for further evaluation and experience until it will be used for clinical application during the middle of 2001.

Material and Method For evaluation, we used the prutotype planning and navigation - System called KR (DesX, Iarnel), which tracks the actual position of the handpiece in real-size. The type, size, position and intentation of the implants are planned based on CT data with IGI Settinger from DesX.

and minimization of the implants are planned based on CT data with 1GI Sethware from DenX Lid. KaVOT9 plantum javas were used for the taxs. Different methods of clotical locations were weal for the different kinds of jave models. For the EWL suggery model an corplic pplitt was respond and clotent Grammic spleres. 3 nmt in diameter were commond to the splitt's actual to the different kinds of jave models. For the EWL suggery model an corplic pplitt was respond and clotent Causained with the artificial landmarks and the digital data were transferred onto the IGI station. The 3D planning of the implantations and the digital data were transferred on the IGI station. The 3D planning of the implantations and the dilling was then seen perpared in 2 model implantations. The mean station of the tax of the tax is the dilling was then corporated in 2 model implantations. The mean station of the implantation and the dilling was then the following coder layer. The mean station of the implantation of the tax is the dilling was determined in the CT same Light mere implant advertical to the occlusion plane was determined in the CT same Light mere implant advertical to the occlusion plane was determined in the CT same. The position of the patient was referenced by registering the landmarks. The spheres as the split and on the jave implant are used an immlantaka. The spheres are tay length or the indicates market uses were drilled carefully while the IGI system's visual and and/o indicates made at the spin the test proceeding there was no to explain the were transferred by registering the landmarks. The spheres are the split due to the CT data were the during the their proceeding there was an documenter. The digital postoperative CT data were that during the their proceeding the wave visual implants are fused on the CT data using the Education.

Insution. In the postpontive CT, the doill heles could be easily need and defined. The doill hele conter-tory position and end position were defined with the software roler teel and the 3D eccentrations of the top and end conter were explored. The same procedure was done with the virtual implants and the deviation between the virtual implant and and hele was calculated.

Results We tested 38 implants within edentifores phantom jews and 8 implants in partially edentifores phantom jews (Table 1a-b). We found im accuracy that has a deviation of 8 mm at best and a deviation of 1.2 mm at weet. For both the deviations and the partially edentificate it is shown that 95% of the deviations are below 1 mm, which coincides with the achievement of the 1 mm accuracy.

Conclusion The ICI system will offer the densist an easy to handle tool, which accumtely transfers the preoperatively defined implant position directly to the patient during the sengical precodure. While evaluating the systems benefits and precision in a phantom study, we found the system's total accuracy equals 1.0 mm.

Acknowledgement This research was performed by members of the Department of Ond and Maxillufacial Saragery, Prot. D. Dr. J. Muchling, University of Heidelberg, at DenX, Moshav Oca 106, Jerusadem 90880, Iarael. The work is being funded partially by the Sonderforedmagabereich 414 "Information Technology in Madeine - Computer and Senser Supported Surgery" of the Deutsche Faschungsgemeinschaft.







today for play while dellarg Enouting the drilling, trailing the most position of the handping and the patient (in final position).

0



deviation of applant and (spec) positions in educations planties prev-