

## PATENT ASSIGNMENT COVER SHEET

Electronic Version v1.1  
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EPAS ID: PAT5768904

<b>SUBMISSION TYPE:</b>	NEW ASSIGNMENT
<b>NATURE OF CONVEYANCE:</b>	ASSIGNMENT
<b>CONVEYING PARTY DATA</b>	
<b>Name</b>	<b>Execution Date</b>
HANSEN MEDICAL INC.	08/23/2018
<b>RECEIVING PARTY DATA</b>	
<b>Name:</b>	AURIS HEALTH, INC.
<b>Street Address:</b>	150 SHORELINE DRIVE
<b>City:</b>	REDWOOD CITY
<b>State/Country:</b>	CALIFORNIA
<b>Postal Code:</b>	94065
<b>PROPERTY NUMBERS Total: 1</b>	
<b>Property Type</b>	<b>Number</b>
<b>Application Number:</b>	16165534
<b>CORRESPONDENCE DATA</b>	
<b>Fax Number:</b>	(949)760-9502
<i>Correspondence will be sent to the e-mail address first; if that is unsuccessful, it will be sent using a fax number, if provided; if that is unsuccessful, it will be sent via US Mail.</i>	
<b>Phone:</b>	9497600404
<b>Email:</b>	efiling@knobbe.com
<b>Correspondent Name:</b>	KNOBBE, MARTENS, OLSON & BEAR, LLP
<b>Address Line 1:</b>	2040 MAIN STREET
<b>Address Line 2:</b>	14TH FLOOR
<b>Address Line 4:</b>	IRVINE, CALIFORNIA 92614
<b>ATTORNEY DOCKET NUMBER:</b>	HM-0160C5 / HMI.023C5
<b>NAME OF SUBMITTER:</b>	RABINDER NARULA
<b>SIGNATURE:</b>	/Rabinder N. Narula/
<b>DATE SIGNED:</b>	10/14/2019
<b>Total Attachments: 19</b>	
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**EXHIBIT A**  
**ASSIGNMENT**

WHEREAS, Hansen Medical, Inc., a Delaware Corporation, having an address at 150 Shoreline Drive, Redwood City, CA 94065 (hereinafter "ASSIGNOR"), owns the entire right, title, and interest to certain new and useful improvements for which ASSIGNOR has filed the issued Letters Patents and applications for Letters Patents in the United States and other jurisdictions listed in Exhibit 1 (hereinafter "the Patents and Patent Applications");

WHEREAS, Auris Health, Inc., a Delaware Corporation, having an address at 150 Shoreline Drive, Redwood City, CA 94065 (hereinafter "ASSIGNEE") desires to acquire the entire right, title, and interest in and to the inventions disclosed in the Patents and Patent Applications:

NOW, THEREFORE, for good and valuable consideration, the receipt of which is hereby acknowledged, ASSIGNOR hereby acknowledges that it has sold, assigned, and transferred, and by these presents does hereby sell, assign, and transfer, unto ASSIGNEE, its successors, legal representatives, and assigns, its entire right, title, and interest throughout the world in, to, and under the Patents and Patent Applications and the inventions disclosed in the Patents and Patent Applications, and all Patents that may be granted thereon, and all provisional applications relating thereto, and all divisions, continuations, reissues, reexaminations, renewals, and extensions thereof, and all rights of priority under International Conventions and applications for Letters Patent that may hereafter be filed for said improvements or for the said Patent Applications in any country or countries foreign to the United States; and ASSIGNOR hereby authorizes and requests the Commissioner of Patents of the United States, and any Official of any country foreign to the United States, whose duty it is to issue patents on applications as aforesaid, to issue all Letters Patent for said improvements and all Letters Patents resulting from the Patents and Patent Applications to ASSIGNEE, its successors, legal representatives, and assigns, in accordance with the terms of this Assignment.

ASSIGNOR does hereby sell, assign, transfer, and convey to ASSIGNEE, its successors, legal representatives, and assigns all claims for damages and all remedies arising out of any violation of the rights assigned hereby that may have accrued prior to the date of assignment to ASSIGNEE, or may accrue hereafter, including, but not limited to, the right to sue for, collect, and retain damages for past infringements of the Letters Patents before or after issuance.

ASSIGNOR hereby covenants and agrees that it will communicate to ASSIGNEE, its successors, legal representatives, and assigns any facts known to ASSIGNOR respecting the Patents and Patent Applications immediately upon becoming aware of those facts, and that it will testify in any legal proceeding involving any of the Patents and Patent Applications, will sign all lawful papers, execute all divisional, continuing, and reissue applications, make all rightful oaths, and will generally do everything possible to aid ASSIGNEE, its successors, legal representatives, and assigns to obtain and enforce the Patents and Patent Applications in all countries.

IN TESTIMONY WHEREOF, I hereunto set my hand and seal this 23<sup>rd</sup> day of August, 2018.

**Assignor (Conveying Party)**

Hansen Medical, Inc.  
150 Shoreline Drive  
Redwood City, CA 94065

By: 

Name: David Styka

Title: Chairman

Date: Aug 23, 2018

**ACKNOWLEDGMENT**

A notary public or other officer completing this certificate verifies only the identity of the individual who signed the document to which this certificate is attached, and not the truthfulness, accuracy, or validity of that document.

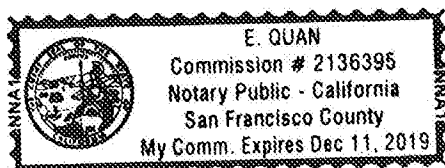
STATE OF CALIFORNIA }  
COUNTY OF SAN MATEO } ss.


On August 23, 2018, before me, E. Quan, notary public, personally appeared David Styka who proved to me on the basis of satisfactory evidence to be the person whose name is subscribed to the within instrument, and acknowledged to me that he/she executed the same in his/her authorized capacity, and that by his/her signature on the instrument the person, or the entity upon behalf of which the person acted, executed the instrument.

I certify under PENALTY OF PERJURY under the laws of the State of California that the foregoing paragraph is true and correct.

WITNESS my hand and official seal.

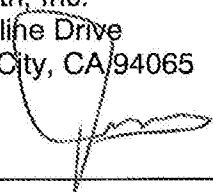
[Seal]



  
Notary Signature

IN TESTIMONY WHEREOF, I hereunto set my hand and seal this 24<sup>th</sup> day of August, 2018.

**Assignee (Receiving Party)**  
Auris Health, Inc.  
150 Shoreline Drive  
Redwood City, CA 94065

By: 

Name: Frederic Moll

Title: Chief Executive Officer

Date: August 24, 2018

**ACKNOWLEDGMENT**

A notary public or other officer completing this certificate verifies only the identity of the individual who signed the document to which this certificate is attached, and not the truthfulness, accuracy, or validity of that document.

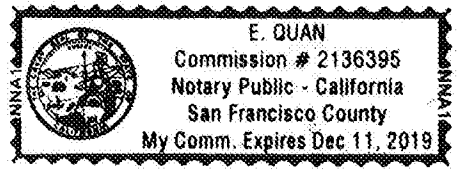
STATE OF CALIFORNIA }  
COUNTY OF SAN MATEO } ss.

On August 24, 2018, before me, E. Quan, notary public, personally appeared Frederic Moll who proved to me on the basis of satisfactory evidence to be the person whose name is subscribed to the within instrument, and acknowledged to me that he/she executed the same in his/her authorized capacity, and that by his/her signature on the instrument the person, or the entity upon behalf of which the person acted, executed the instrument.

I certify under PENALTY OF PERJURY under the laws of the State of California that the foregoing paragraph is true and correct.

WITNESS my hand and official seal.

[Seal]



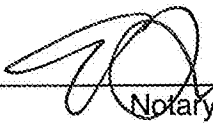
  
Notary Signature

EXHIBIT 1

Issued Patents and Filed Patent Applications

Auris Ref. No.	Country	Title	Application No.	Filing Date	Patent No.	Grant Date
HM-0001C2	US	ARTICULATED APPARATUS FOR TELEMANIPULATOR SYSTEM	09/827,503	Apr 6, 2001	6,432,112	Aug 13, 2002
HM-0001D1	US	ARTICULATED APPARATUS FOR TELEMANIPULATOR SYSTEM	09/746,853	Dec 21, 2000	6,692,485	Feb 17, 2004
HM-0002C2	US	SURGICAL INSTRUMENT	10/977,796	Oct 29, 2004	7,744,622	Jun 29, 2010
HM-0002EP	EP	SURGICAL INSTRUMENT	00928917.4	May 9, 2000	EP1176921	Feb 23, 2011
HM-0002EPD2	EP	SURGICAL INSTRUMENT	02075952.8	May 9, 2000	EP1224919	Jul 5, 2006
HM-0002EPD3	EP	FLEXIBLE INSTRUMENT	02709537.1	Feb 15, 2002	EP1303228	Sep 26, 2012
HM-0002EPD4	EP	FLEXIBLE INSTRUMENT	10183901.7	Feb 15, 2002	EP2298220	Jun 8, 2016
HM-0002EPD4DE	DE	FLEXIBLE INSTRUMENT	60248133.3	Feb 15, 2002	60248133.3	Jun 8, 2016
HM-0002EPD4FR	FR	FLEXIBLE INSTRUMENT	10183901.7	Feb 15, 2002	EP2298220	Jun 8, 2016
HM-0002EPD4GB	GB	FLEXIBLE INSTRUMENT	10183901.7	Feb 15, 2002	EP2298220	Jun 8, 2016
HM-0002EPD4NL	NL	FLEXIBLE INSTRUMENT	10183901.7	Feb 15, 2002	EP2298220	Jun 8, 2016
HM-0002EPD5	EP	FLEXIBLE INSTRUMENT	16168621.7	Feb 15, 2002		
HM-0002X1	US	SURGICAL INSTRUMENT	09/827,643	Apr 6, 2001	6,554,844	Apr 29, 2003
HM-0005	US	APPARATUS AND METHODS FOR TREATING TISSUE	09/602,436	Jun 23, 2000	6,669,687	Dec 30, 2003
HM-0005DE	DE	APPARATUS AND METHODS FOR TREATING TISSUE	00944803.6	Jun 23, 2000	60044531.3-08	Jun 9, 2010
HM-0005EP	EP	APPARATUS AND METHODS FOR TREATING TISSUE	00944803.6	Jun 23, 2000	EP1198213	Jun 9, 2010
HM-0005GB	GB	APPARATUS AND METHODS FOR TREATING TISSUE	00944803.6	Jun 23, 2000	EP1198213	Jun 9, 2010
HM-0005JP	JP	APPARATUS AND METHODS FOR TREATING TISSUE	2001-505831	Jun 23, 2000	4576521	Sep 3, 2010
HM-0018C1	US	APPARATUS AND METHODS FOR TREATING TISSUE	10/669,204	Sep 23, 2003	7,217,284	May 15, 2007

Auris Ref. No.	Country	Title	Application No.	Filing Date	Patent No.	Grant Date
HM-0018X1	US	APPARATUS AND METHODS FOR TREATING TISSUE	09/898,726	Jul 3, 2001	6,626,899	Sep 30, 2003
HM-0024X1X1	US	ROBOTICALLY CONTROLLED SURGICAL INSTRUMENTS	10/715,339	Nov 17, 2003	7,699,835	Apr 20, 2010
HM-0028X1	US	SURGICAL INSTRUMENT	10/008,871	Nov 16, 2001	6,843,793	Jan 18, 2005
HM-0030C1	US	FLEXIBLE INSTRUMENT	11/762,768	Jun 13, 2007	7,918,861	Apr 5, 2011
HM-0030C2	US	FLEXIBLE INSTRUMENT	11/762,770	Jun 13, 2007	7,867,241	Jan 11, 2011
HM-0030C3	US	FLEXIBLE INSTRUMENT	11/762,772	Jun 13, 2007	8,114,097	Feb 14, 2012
HM-0030C4	US	FLEXIBLE INSTRUMENT	11/762,773	Jun 14, 2007	7,905,828	Mar 15, 2011
HM-0030C7	US	FLEXIBLE INSTRUMENT	12/023,865	Jan 31, 2008	7,931,586	Apr 26, 2011
HM-0030C8	US	FLEXIBLE INSTRUMENT	13/361,371	Jan 30, 2012	8,414,598	Apr 9, 2013
HM-0030X1	US	FLEXIBLE INSTRUMENT	10/012,586	Nov 16, 2001	7,371,210	May 13, 2008
HM-0032X1	US	FLEXIBLE INSTRUMENT	10/010,150	Nov 16, 2001	7,214,230	May 8, 2007
HM-0033C1	US	SURGICAL INSTRUMENTS	11/562,960	Nov 22, 2006	7,789,875	Sep 7, 2010
HM-0033X1	US	SURGICAL INSTRUMENT	10/012,845	Nov 16, 2001	7,169,141	Jan 30, 2007
HM-0035X1	US	MEDICAL MAPPING SYSTEM	10/034,871	Dec 21, 2001	6,810,281	Oct 26, 2004
HM-0037X1	US	INTERCHANGEABLE SURGICAL INSTRUMENT	10/077,233	Feb 15, 2002	7,297,142	Nov 20, 2007
HM-0037X1C1	US	INTERCHANGEABLE SURGICAL INSTRUMENT	11/762,755	Jun 13, 2007	7,758,569	Jul 20, 2010
HM-0037X1C2	US	INTERCHANGEABLE SURGICAL INSTRUMENT	11/762,758	Jun 13, 2007	7,901,399	Mar 8, 2011
HM-0037X1C3	US	INTERCHANGEABLE SURGICAL INSTRUMENT	13/010,657	Jan 20, 2011	8,303,576	Nov 6, 2012
HM-0039D1	US	INTERCHANGEABLE INSTRUMENT	11/014,687	Dec 16, 2004	7,604,642	Oct 20, 2009
HM-0039X1	US	INTERCHANGEABLE FLUID INSTRUMENT	10/097,923	Mar 15, 2002	6,860,878	Mar 1, 2005
HM-0041C1	US	APPARATUS AND METHODS FOR TREATING TISSUE	11/622,442	Jan 11, 2007	7,562,660	Jul 21, 2009
HM-0041C2	US	APPARATUS AND METHODS FOR TREATING TISSUE	12/489,258	Jun 22, 2009	8,333,204	Dec 18, 2012
HM-0041C3	US	APPARATUS AND METHODS FOR TREATING TISSUE	13/212,842	Aug 18, 2011	8,523,883	Sep 3, 2013

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HM-0041X1	US	APPARATUS AND METHODS FOR TREATING TISSUE	10/188,509	Jul 3, 2002	7,186,262	Mar 6, 2007
HM-0044C3	US	ROBOTIC MEDICAL INSTRUMENT SYSTEM	11/762,726	Jun 13, 2007	7,959,557	Jun 14, 2011
HM-0044C4	US	ROBOTIC MEDICAL INSTRUMENT SYSTEM	11/762,730	Jun 13, 2007	8,671,950	Mar 18, 2014
HM-0046	US	SURGICAL INSTRUMENT COUPLING MECHANISM	10/302,804	Nov 21, 2002	7,331,967	Feb 19, 2008
HM-0046C1	US	SURGICAL INSTRUMENT COUPLING MECHANISM	11/762,743	Jun 13, 2007	7,947,050	May 24, 2011
HM-0046C2	US	SURGICAL INSTRUMENT COUPLING MECHANISM	11/762,745	Jun 13, 2007	7,947,051	May 24, 2011
HM-0047C1	US	COAXIAL CATHETER SYSTEM	11/467,886	Aug 28, 2006	7,766,894	Aug 3, 2010
HM-0047C2	US	COAXIAL CATHETER SYSTEM	11/762,749	Jun 13, 2007	8,187,229	May 29, 2012
HM-0047C3	US	COAXIAL CATHETER SYSTEM	11/762,751	Jun 13, 2007	7,955,316	Jun 7, 2011
HM-0047C4	US	COAXIAL CATHETER SYSTEM	11/762,748	Jun 13, 2007	7,727,185	Jun 1, 2010
HM-0047C5	US	COAXIAL CATHETER SYSTEM	12/023,943	Jan 31, 2008	8,603,068	Dec 10, 2013
HM-0049C1	US	CATHETER DRIVER SYSTEM	12/111,119	Apr 28, 2008	8,684,952	Apr 1, 2014
HM-0049C4	US	CATHETER DRIVER SYSTEM	15/465,403	Mar 21, 2017		
HM-0049X1	US	CATHETER DRIVER SYSTEM	10/270,743	Oct 11, 2002	8,414,505	Apr 9, 2013
HM-0050X1C1	US	ROBOTICALLY CONTROLLED MEDICAL INSTRUMENT WITH A FLEXIBLE SECTION	10/976,066	Oct 28, 2004	7,608,083	Oct 27, 2009
HM-0050X1C2	US	ROBOTICALLY CONTROLLED MEDICAL INSTRUMENT	12/023,981	Jan 31, 2008	7,744,608	Jun 29, 2010
HM-0050X1C3	US	ROBOTICALLY CONTROLLED MEDICAL INSTRUMENT	12/024,013	Jan 31, 2008	7,819,884	Oct 26, 2010
HM-0050X1C4	US	ROBOTICALLY CONTROLLED MEDICAL INSTRUMENT	12/024,039	Jan 31, 2008	7,854,738	Dec 21, 2010
HM-0052	US	SURGICAL INSTRUMENT DESIGN	10/858,822	Jun 1, 2004	8,007,511	Aug 30, 2011
HM-0054	US	SYSTEM AND METHOD FOR 3-D IMAGING	10/923,660	Aug 20, 2004	7,618,371	Nov 17, 2009



Auris Ref. No.	Country	Title	Application No.	Filing Date	Patent No.	Grant Date
HM-0054C1	US	SYSTEM AND METHOD FOR 3-D IMAGING	12/577,086	Oct 9, 2009	7,935,059	May 3, 2011
HM-0054C2	US	SYSTEM AND METHOD FOR 3-D IMAGING	13/073,527	Mar 28, 2011	8,388,538	Mar 5, 2013
HM-0055	US	BALLOON VISUALIZATION FOR TRAVERSING A TISSUE WALL	10/949,032	Sep 24, 2004	8,172,747	May 8, 2012
HM-0058	US	ROBOTIC CATHETER SYSTEM	11/073,363	Mar 4, 2005	7,972,298	Jul 5, 2011
HM-0058C1	US	ROBOTIC CATHETER SYSTEM	13/118,293	May 27, 2011	8,409,136	Apr 2, 2013
HM-0058C2	US	ROBOTIC CATHETER SYSTEM	13/118,309	May 27, 2011	8,394,054	Mar 12, 2013
HM-0058C3	US	ROBOTIC CATHETER SYSTEM	13/782,262	Mar 1, 2013	8,974,408	Mar 10, 2015
HM-0058C4	US	ROBOTIC CATHETER SYSTEM	14/579,530	Dec 22, 2014	9,629,682	Apr 25, 2017
HM-0058C5	US	ROBOTIC CATHETER SYSTEM	15/469,382	Mar 24, 2017		
HM-0058EPD1	EP	ROBOTIC CATHETER SYSTEM	11169157.2	Mar 4, 2005	EP2384715	Jul 8, 2015
HM-0058EPD1DE	DE	ROBOTIC CATHETER SYSTEM	602005046949.4	Mar 4, 2005	EP2384715	Jul 8, 2015
HM-0058EPD1FR	FR	ROBOTIC CATHETER SYSTEM	11169157.2	Mar 4, 2005	EP2384715	Jul 8, 2015
HM-0058EPD1GB	GB	ROBOTIC CATHETER SYSTEM	11169157.2	Mar 4, 2005	EP2384715	Jul 8, 2015
HM-0058JP	JP	ROBOTIC CATHETER SYSTEM	2007-502015	Mar 4, 2005	JP4755638	Jun 3, 2011
HM-0061DE	DE	ROBOTICALLY CONTROLLED INTRAVASCULAR TISSUE INJECTION SYSTEM	05786497.7	Aug 12, 2005	602005017792.2-08	Nov 18, 2009
HM-0061EP	EP	ROBOTICALLY CONTROLLED INTRAVASCULAR TISSUE INJECTION SYSTEM	05786497.7	Aug 12, 2005	EP1776057	Nov 18, 2009
HM-0061GB	GB	ROBOTICALLY CONTROLLED INTRAVASCULAR TISSUE INJECTION SYSTEM	05786497.7	Aug 12, 2005	EP1776057	Nov 18, 2009
HM-0062US1	US	SUPPORT ASSEMBLY FOR ROBOTIC CATHETER SYSTEM	11/173,812	Jul 1, 2005	7,789,874	Sep 7, 2010
HM-0062US1C1	US	SUPPORT ASSEMBLY FOR ROBOTIC CATHETER SYSTEM	12/859,198	Aug 18, 2010	8,968,333	Mar 3, 2015
HM-0062US2	US	ROBOTIC CATHETER SYSTEM	11/418,398	May 3, 2006	7,963,288	Jun 21, 2011

Auris Ref. No.	Country	Title	Application No.	Filing Date	Patent No.	Grant Date
HM-0063	US	ROBOTIC CATHETER SYSTEM AND METHODS	11/481,433	Jul 3, 2006	8,052,636	Nov 8, 2011
HM-0063C2	US	ROBOTIC CATHETER SYSTEM AND METHODS	13/225,324	Sep 2, 2011	8,257,303	Sep 4, 2012
HM-0063C3	US	ROBOTIC CATHETER SYSTEM AND METHODS	13/358,468	Jan 25, 2012	8,617,102	Dec 31, 2013
HM-0063C4	US	ROBOTIC CATHETER SYSTEM AND METHODS	14/074,544	Nov 7, 2013	8,801,661	Aug 12, 2014
HM-0063C5	US	ROBOTIC CATHETER SYSTEM AND METHODS	14/308,969	Jun 19, 2014	9,457,168	Oct 4, 2016
HM-0063C6	US	ROBOTIC CATHETER SYSTEM AND METHODS	15/283,793	Oct 3, 2016		
HM-0063DE	DE	ROBOTIC CATHETER SYSTEM	06786388.6	Jul 3, 2006	EP1906858	Nov 16, 2016
HM-0063EP	EP	ROBOTIC CATHETER SYSTEM	06786388.6	Jul 3, 2006	EP1906858	Nov 16, 2016
HM-0063FR	FR	ROBOTIC CATHETER SYSTEM	06786388.6	Jul 3, 2006	EP1906858	Nov 16, 2016
HM-0063GB	GB	ROBOTIC CATHETER SYSTEM	06786388.6	Jul 3, 2006	EP1906858	Nov 16, 2016
HM-0064	US	INSTRUMENT DRIVER FOR ROBOTIC CATHETER SYSTEM	11/176,954	Jul 6, 2005	8,021,326	Sep 20, 2011
HM-0065	US	METHODS USING A ROBOTIC CATHETER SYSTEM	11/179,007	Jul 6, 2005	7,850,642	Dec 14, 2010
HM-0066	US	ROBOTIC CATHETER SYSTEM	11/176,957	Jul 6, 2005	7,974,681	Jul 5, 2011
HM-0066X1	US	SYSTEM AND METHOD FOR DENATURING AND FIXING COLLAGENOUS TISSUE	11/185,432	Jul 19, 2005	7,976,539	Jul 12, 2011
HM-0066X1D1	US	SYSTEM AND METHOD FOR DENATURING AND FIXING COLLAGENOUS TISSUE	13/044,318	Mar 9, 2011	8,926,603	Jan 6, 2015
HM-0067	US	ROBOTICALLY CONTROLLED INTRAVASCULAR TISSUE INJECTION SYSTEM	11/202,925	Aug 12, 2005	8,005,537	Aug 23, 2011

Auris Ref. No.	Country	Title	Application No.	Filing Date	Patent No.	Grant Date
HM-0067C1	US	ROBOTICALLY CONTROLLED INTRAVASCULAR TISSUE INJECTION SYSTEM	13/188,312	Jul 21, 2011	8,311,626	Nov 13, 2012
HM-0069	US	METHODS, DEVICES, AND KITS FOR TREATING MITRAL VALVE PROLAPSE	11/286,037	Nov 23, 2005	7,632,308	Dec 15, 2009
HM-0069C1	US	METHODS, DEVICES, AND KITS FOR TREATING MITRAL VALVE PROLAPSE	12/608,849	Oct 29, 2009	8,545,551	Oct 1, 2013
HM-0070US1	US	ROBOTIC CATHETER SYSTEM AND METHODS	11/637,951	Dec 11, 2006	8,190,238	May 29, 2012
HM-0070US2	US	ROBOTIC CATHETER SYSTEM AND METHODS	11/640,099	Dec 14, 2006	8,498,691	Jul 30, 2013
HM-0073CN	CN	AUTOMATIC INSTRUMENT SYSTEM	200780017763.5	May 17, 2007	ZL 200780017763.5	Aug 17, 2011
HM-0073EP	EP	ROBOTIC INSTRUMENT SYSTEM	07795082.2	May 17, 2007	EP2023845	Jul 7, 2010
HM-0073EPD1	EP	ROBOTIC INSTRUMENT SYSTEM	10150323.3	May 17, 2007	EP2177174	Jul 24, 2013
HM-0073EPD1DE	DE	ROBOTIC INSTRUMENT SYSTEM	10150323.3	May 17, 2007	602007031928.5	Jul 24, 2013
HM-0073EPD1FR	FR	ROBOTIC INSTRUMENT SYSTEM	10150323.3	May 17, 2007	EP2177174	Jul 24, 2013
HM-0073EPD1GB	GB	ROBOTIC INSTRUMENT SYSTEM	10150323.3	May 17, 2007	EP2177174	Jul 24, 2013
HM-0075	US	SYSTEMS AND METHODS FOR PERFORMING MINIMALLY INVASIVE PROCEDURES	11/833,969	Aug 3, 2007	8,409,172	Apr 2, 2013
HM-0076	US	SYSTEMS AND METHODS FOR THREE-DIMENSIONAL ULTRASOUND MAPPING	11/906,746	Oct 2, 2007	8,041,413	Oct 18, 2011
HM-0076C1	US	SYSTEMS AND METHODS FOR THREE-DIMENSIONAL ULTRASOUND MAPPING	13/274,141	Oct 14, 2011	8,285,364	Oct 9, 2012
HM-0076DE	DE	SYSTEMS FOR THREE DIMENSIONAL ULTRASOUND MAPPING	07839220.6	Oct 2, 2007	602007012450.6-08	Feb 9, 2011
HM-0076EP	EP	SYSTEMS FOR THREE DIMENSIONAL ULTRASOUND MAPPING	07839220.6	Oct 2, 2007	EP2068716	Feb 9, 2011

Auris Ref. No.	Country	Title	Application No.	Filing Date	Patent No.	Grant Date
HM-0076GB	GB	SYSTEMS FOR THREE DIMENSIONAL ULTRASOUND MAPPING	07839220.6	Oct 2, 2007	EP2068716	Feb 9, 2011
HM-0077	US	ROBOTIC CATHETER SYSTEM AND METHODS	11/972,581	Jan 10, 2008	8,108,069	Jan 31, 2012
HM-0078C1	US	ROBOTIC INSTRUMENT SYSTEMS CONTROLLED USING KINEMATICS AND MECHANICS MODELS	14/734,171	Jun 9, 2015		
HM-0078EP	EP	ROBOTIC INSTRUMENT SYSTEMS CONTROLLED USING KINEMATICS AND MECHANICS MODELS	08728601.9	Jan 30, 2008		
HM-0082	US	APPARATUS FOR MEASURING DISTAL FORCES ON A WORKING INSTRUMENT	11/678,001	Feb 22, 2007	8,092,397	Jan 10, 2012
HM-0082EP	EP	SYSTEM AND APPARATUS FOR MEASURING DISTAL FORCES ON A WORKING INSTRUMENT	07757358.2	Feb 22, 2007	EP1986563	Dec 26, 2012
HM-0082JP	JP	SYSTEM AND APPARATUS FOR MEASURING DISTAL FORCES ON A WORKING INSTRUMENT	2008-556546	Feb 22, 2007	JP5236502	Apr 5, 2013
HM-0083	US	METHOD OF SENSING FORCES ON A WORKING INSTRUMENT	11/678,016	Feb 22, 2007	8,052,621	Nov 8, 2011
HM-0083C1	US	METHOD OF SENSING FORCES ON A WORKING INSTRUMENT	13/251,370	Oct 3, 2011	8,388,556	Mar 5, 2013
HM-0084	US	APPARATUS SYSTEMS AND METHODS FOR FLUSHING GAS FROM A CATHETER OF A ROBOTIC CATHETER SYSTEM	12/077,796	Mar 19, 2008	7,922,693	Apr 12, 2011
HM-0084D1	US	APPARATUS SYSTEMS AND METHODS FOR FLUSHING GAS FROM A CATHETER OF A ROBOTIC CATHETER SYSTEM	13/039,181	Mar 2, 2011	8,377,077	Feb 19, 2013
HM-0085	US	ROBOTIC CATHETER SYSTEMS AND METHODS	12/079,500	Mar 26, 2008	8,391,957	Mar 5, 2013
HM-0085D1	US	ROBOTIC CATHETER SYSTEMS AND METHODS	13/458,930	Apr 27, 2012	9,066,740	Jun 30, 2015

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HM-0085DE	DE	ROBOTIC CATHETER SYSTEM AND METHODS	08742307.5	Mar 26, 2008	EP2139422	Oct 26, 2016
HM-0085EP	EP	ROBOTIC CATHETER SYSTEM AND METHODS	08742307.5	Mar 26, 2008	EP2139422	Oct 26, 2016
HM-0085FR	FR	ROBOTIC CATHETER SYSTEM AND METHODS	08742307.5	Mar 26, 2008	EP2139422	Oct 26, 2016
HM-0085GB	GB	ROBOTIC CATHETER SYSTEM AND METHODS	08742307.5	Mar 26, 2008	EP2139422	Oct 26, 2016
HM-0085NL	NL	ROBOTIC CATHETER SYSTEM AND METHODS	08742307.5	Mar 26, 2008	EP2139422	Oct 26, 2016
HM-0089	US	SYSTEM AND METHOD FOR DETERMINING ELECTRODE-TISSUE CONTACT BASED ON AMPLITUDE MODULATION OF SENSED SIGNAL	11/762,778	Jun 14, 2007	8,160,690	Apr 17, 2012
HM-0089C1	US	SYSTEM AND METHOD FOR DETERMINING ELECTRODE-TISSUE CONTACT BASED ON AMPLITUDE MODULATION OF SENSED SIGNAL	13/423,034	Mar 16, 2012	8,489,184	Jul 16, 2013
HM-0094	US	OPTICAL FIBER GRATING SENSORS AND METHODS OF MANUFACTURE	12/236,478	Sep 23, 2008	8,989,528	Mar 24, 2015
HM-0098	US	MOUNTING SUPPORT ASSEMBLY FOR SUSPENDING A MEDICAL INSTRUMENT DRIVER ABOVE AN OPERATING TABLE	12/024,883	Feb 1, 2008	8,146,874	Apr 3, 2012
HM-0098C2	US	MOUNTING SUPPORT ASSEMBLY FOR SUSPENDING A MEDICAL INSTRUMENT DRIVER ABOVE AN OPERATING TABLE	13/910,903	Jun 5, 2013	9,566,201	Feb 14, 2017
HM-0103DE	DE	ROBOTIC MEDICAL INSTRUMENT SYSTEM	08730065.3	Feb 15, 2008	602008003536.0	Nov 17, 2010
HM-0103EP	EP	ROBOTIC MEDICAL INSTRUMENT SYSTEM	08730065.3	Feb 15, 2008	EP2124800	Nov 17, 2010
HM-0103GB	GB	ROBOTIC MEDICAL INSTRUMENT SYSTEM	08730065.3	Feb 15, 2008	EP2124800	Nov 17, 2010

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HM-0105C1	US	ROBOTIC ABLATION CATHETER	15/142,663	Apr 29, 2016		
HM-0106	US	SYSTEMS, METHODS AND DEVICES FOR CORRELATING REFERENCE LOCATIONS USING IMAGE DATA	12/428,997	Apr 23, 2009	8,270,694	Sep 18, 2012
HM-0113	US	ROTATIONAL APPARATUS SYSTEM AND METHOD FOR A ROBOTIC INSTRUMENT SYSTEM	12/126,814	May 23, 2008	8,409,234	Apr 2, 2013
HM-0115	US	STERILE INTERFACE APPARATUS	12/614,349	Nov 6, 2009	8,720,448	May 13, 2014
HM-0116	US	APPARATUS AND METHOD FOR SENSING FORCE	12/269,684	Nov 12, 2008	8,083,691	Dec 27, 2011
HM-0116C1	US	APPARATUS AND METHOD FOR SENSING FORCE ON A ROBOTICALLY CONTROLLED MEDICAL INSTRUMENT	13/756,239	Jan 31, 2013	9,480,820	Nov 1, 2016
HM-0116X1	US	APPARATUS AND METHOD FOR SENSING FORCE ON A ROBOTICALLY CONTROLLED MEDICAL INSTRUMENT	12/641,145	Dec 17, 2009	8,372,019	Feb 12, 2013
HM-0120	US	MODULAR INTERFACES AND DRIVE ACTUATION THROUGH BARRIER	12/352,551	Jan 12, 2009	8,602,031	Dec 10, 2013
HM-0120C1	US	MODULAR INTERFACES AND DRIVE ACTUATION THROUGH BARRIER	14/075,255	Nov 8, 2013	9,204,933	Dec 8, 2015
HM-0122	US	FLEXIBLE AND STEERABLE ELONGATE INSTRUMENTS WITH SHAPE CONTROL AND SUPPORT ELEMENTS	12/432,683	Apr 29, 2009	9,254,123	Feb 9, 2016
HM-0122C1	US	FLEXIBLE AND STEERABLE ELONGATE INSTRUMENTS WITH SHAPE CONTROL AND SUPPORT ELEMENTS	15/017,147	Feb 5, 2016		
HM-0122DE	DE	FLEXIBLE AND STEERABLE ELONGATE INSTRUMENTS WITH SHAPE CONTROL AND SUPPORT ELEMENTS	602010035212.9	Apr 29, 2010	602010035212.9	Aug 3, 2016

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HM-0122EP	EP	FLEXIBLE AND STEERABLE ELONGATE INSTRUMENTS WITH SHAPE CONTROL AND SUPPORT ELEMENTS	10770366.2	Apr 29, 2010	EP2424609	Aug 3, 2016
HM-0122EPD1	EP	FLEXIBLE AND STEERABLE ELONGATE INSTRUMENTS WITH SHAPE CONTROL AND SUPPORT ELEMENTS	16175536.8	Apr 29, 2010		
HM-0122FR	FR	FLEXIBLE AND STEERABLE ELONGATE INSTRUMENTS WITH SHAPE CONTROL AND SUPPORT ELEMENTS	10770366.2	Apr 29, 2010	2424609	Aug 3, 2016
HM-0122GB	GB	FLEXIBLE AND STEERABLE ELONGATE INSTRUMENTS WITH SHAPE CONTROL AND SUPPORT ELEMENTS	10770366.2	Apr 29, 2010	2424609	Aug 3, 2016
HM-0122NL	NL	FLEXIBLE AND STEERABLE ELONGATE INSTRUMENTS WITH SHAPE CONTROL AND SUPPORT ELEMENTS	10770366.2	Apr 29, 2010	2424609	Aug 3, 2016
HM-0128	US	AUTOMATED ALIGNMENT	12/507,777	Jul 22, 2009	8,317,746	Nov 27, 2012
HM-0128C1	US	AUTOMATED ALIGNMENT	13/678,280	Nov 15, 2012	8,657,781	Feb 25, 2014
HM-0131	US	FIBER OPTIC INSTRUMENT SENSING SYSTEM	12/822,876	Jun 24, 2010	8,460,236	Jun 11, 2013
HM-0131EP	EP	FIBER OPTIC INSTRUMENT SENSING SYSTEM	11799017.6	Jun 24, 2011		
HM-0132	US	METHODS AND DEVICES FOR CONTROLLING A SHAPEABLE MEDICAL DEVICE	12/823,032	Jun 24, 2010	8,672,837	Mar 18, 2014
HM-0132D1	US	METHODS AND DEVICES FOR CONTROLLING A SHAPEABLE MEDICAL DEVICE	14/164,961	Jan 27, 2014		
HM-0137DE	DE	ROBOTICALLY CONTROLLED STEERABLE CATHETERS	602011028373.1	Sep 16, 2011	602011028373.1	Jul 20, 2016
HM-0137EP	EP	ROBOTICALLY CONTROLLED STEERABLE CATHETERS	11761231.7	Sep 16, 2011	EP2615992	Jul 20, 2016

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HM-0137EPD1	EP	ROBOTICALLY CONTROLLED STEERABLE CATHETERS	16180007.3	Sep 16, 2011		
HM-0137FR	FR	ROBOTICALLY CONTROLLED STEERABLE CATHETERS	11761231.7	Sep 16, 2011	EP2615992	Jul 20, 2016
HM-0137GB	GB	ROBOTICALLY CONTROLLED STEERABLE CATHETERS	11761231.7	Sep 16, 2011	EP2615992	Jul 20, 2016
HM-0141C1	US	SYSTEMS AND METHODS FOR POSITIONING AN ELONGATE MEMBER INSIDE A BODY	14/603,836	Jan 23, 2015		
HM-0142	US	ANTI-BUCKLING MECHANISMS AND METHODS	13/174,563	Jun 30, 2011	8,961,533	Feb 24, 2015
HM-0144	US	STEERABLE CATHETERS	13/173,994	Jun 30, 2011	8,827,948	Sep 9, 2014
HM-0145	US	SYSTEMS AND METHODS FOR MANIPULATING AN ELONGATE MEMBER	13/174,605	Jun 30, 2011	9,314,306	Apr 19, 2016
HM-0146EP	EP	SYSTEMS AND METHODS UTILIZING SHAPE SENSING FIBERS	12819991.6	Jul 25, 2012		
HM-0148	US	APPARATUS AND METHODS FOR FIBER INTEGRATION AND REGISTRATION	13/314,057	Dec 7, 2011	9,138,166	Sep 22, 2015
HM-0148C2	US	APPARATUS AND METHODS FOR FIBER INTEGRATION AND REGISTRATION	15/258,470	Sep 7, 2016		
HM-0150C1	US	SYSTEM AND METHOD FOR ENDOLUMINAL AND TRANSLUMENAL THERAPY	14/685,089	Apr 13, 2015	9,358,076	Jun 7, 2016
HM-0150C2	US	SYSTEM AND METHOD FOR ENDOLUMINAL AND TRANSLUMENAL THERAPY	15/174,384	Jun 6, 2016		
HM-0151	US	CATHETER HAVING UNIRAIL PULLWIRE ARCHITECTURE	13/687,275	Nov 28, 2012	8,894,610	Nov 25, 2014
HM-0151DE	DE	CATHETER HAVING UNIRAIL PULLWIRE ARCHITECTURE	602013007234.5	Nov 21, 2013	602013007234.5	May 4, 2016



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HM-0151EP	EP	CATHETER HAVING UNIRAIL PULLWIRE ARCHITECTURE	13193922.5	Nov 21, 2013	EP2737922	May 4, 2016
HM-0151EPD1	EP	CATHETER HAVING UNIRAIL PULLWIRE ARCHITECTURE	16167501.2	Nov 21, 2013		
HM-0151FR	FR	CATHETER HAVING UNIRAIL PULLWIRE ARCHITECTURE	13193922.5	Nov 21, 2013	EP2737922	May 4, 2016
HM-0151GB	GB	CATHETER HAVING UNIRAIL PULLWIRE ARCHITECTURE	13193922.5	Nov 21, 2013	EP2737922	May 4, 2016
HM-0152C1	US	METHOD OF ANCHORING PULLWIRE DIRECTLY ARTICULATABLE REGION IN CATHETER	14/844,099	Sep 3, 2015		
HM-0153	US	BRAIDING DEVICE FOR CATHETER HAVING ACUATELY VARYING PULLWIRES	13/687,319	Nov 28, 2012	8,671,817	Mar 18, 2014
HM-0154	US	INFINITELY ROTATABLE TOOL WITH FINITE ROTATING DRIVE SHAFTS	13/788,440	Mar 7, 2013	9,668,814	Jun 6, 2017
HM-0154D1	US	INFINITELY ROTATABLE TOOL WITH FINITE ROTATING DRIVE SHAFTS	15/613,032	Jun 2, 2017		
HM-0155	US	SLIDER CONTROL OF CATHETERS AND WIRES	14/201,582	Mar 7, 2014	9,532,840	Jan 3, 2017
HM-0158	US	INTEGRATED CATHETER AND GUIDE WIRE CONTROLLER	13/800,261	Mar 13, 2013	9,566,414	Feb 14, 2017
HM-0158C1	US	INTEGRATED CATHETER AND GUIDE WIRE CONTROLLER	15/400,656	Jan 6, 2017		
HM-0159	US	SELECTIVE GRIP DEVICE FOR DRIVE MECHANISM	13/801,957	Mar 13, 2013		
HM-0160	US	REDUCING INCREMENTAL MEASUREMENT SENSOR ERROR	14/208,514	Mar 13, 2014	9,057,600	Jun 16, 2015
HM-0160C1	US	REDUCING INCREMENTAL MEASUREMENT SENSOR ERROR	14/712,587	May 14, 2015	9,289,578	Mar 22, 2016

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HM-0160C3	US	REDUCING INCREMENTAL MEASUREMENT SENSOR ERROR	15/387,347	Dec 21, 2016	9,844,353	Dec 19, 2017
HM-0160C4	US	REDUCING INCREMENTAL MEASUREMENT SENSOR ERROR	15/844,420	Dec 15, 2017		
HM-0164	US	ACTIVE DRIVES FOR ROBOTIC CATHETER MANIPULATORS	13/803,535	Mar 14, 2013	9,326,822	May 3, 2016
HM-0164C1	US	ACTIVE DRIVES FOR ROBOTIC CATHETER MANIPULATORS	15/142,930	Apr 29, 2016		
HM-0165C1	US	ACTIVE DRIVES FOR ROBOTIC CATHETER MANIPULATORS	15/243,566	Aug 22, 2016		
HM-0167	US	TORQUE-BASED CATHETER ARTICULATION	13/828,342	Mar 14, 2013	9,173,713	Nov 3, 2015
HM-0167C1	US	TORQUE-BASED CATHETER ARTICULATION	14/867,980	Sep 28, 2015	9,636,483	May 2, 2017
HM-0167C2	US	TORQUE-BASED CATHETER ARTICULATION	15/467,451	Mar 23, 2017		
HM-0167EP	EP	TORQUE-BASED CATHETER ARTICULATION	14160090.8	Mar 14, 2014		
HM-0167X1	US	CATHETER TENSION SENSING	14/214,711	Mar 15, 2014	9,498,601	Nov 22, 2016
HM-0167X1C1	US	CATHETER TENSION SENSING	15/357,537	Nov 21, 2016		
HM-0171	US	CATHETER INSERTION SYSTEM AND METHOD OF FABRICATION	13/832,352	Mar 15, 2013		
HM-0171EP	EP	CATHETER INSERTION SYSTEM AND METHOD OF FABRICATION	14160093.2	Mar 14, 2014		
HM-0172	US	SYSTEMS AND METHODS FOR LOCALIZING, TRACKING AND/OR CONTROLLING MEDICAL INSTRUMENTS	13/832,586	Mar 15, 2013	9,629,595	Apr 25, 2017
HM-0172C1	US	SYSTEMS AND METHODS FOR LOCALIZING, TRACKING AND/OR CONTROLLING MEDICAL INSTRUMENTS	15/466,565	Mar 22, 2017		
HM-0173C1	US	INPUT DEVICE FOR CONTROLLING A CATHETER	15/393,898	Dec 29, 2016		

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HM-0175	US	FLEXIBLE INSTRUMENT LOCALIZATION FROM BOTH REMOTE AND ELONGATION SENSORS	13/833,733	Mar 15, 2013	9,271,663	Mar 1, 2016
HM-0175C1	US	FLEXIBLE INSTRUMENT LOCALIZATION FROM BOTH REMOTE AND ELONGATION SENSORS	15/056,652	Feb 29, 2016		
HM-0176	US	TOUCH-FREE CATHETER USER INTERFACE CONTROLLER	13/833,482	Mar 15, 2013	9,498,291	Nov 22, 2016
HM-0176C1	US	TOUCH-FREE CATHETER USER INTERFACE CONTROLLER	15/357,298	Nov 21, 2016	9,827,061	Nov 28, 2017
HM-0177	US	ROTATIONAL SUPPORT FOR AN ELONGATE MEMBER	13/833,531	Mar 15, 2013	9,452,018	Sep 27, 2016
HM-0177C1	US	ROTATIONAL SUPPORT FOR AN ELONGATE MEMBER	15/270,592	Sep 20, 2016		
HM-0178C1	US	ACTIVE DRIVE MECHANISM FOR SIMULTANEOUS ROTATION AND TRANSLATION	15/359,886	Nov 23, 2016		
HM-0178EP	EP	ACTIVE DRIVE MECHANISM FOR SIMULTANEOUS ROTATION AND TRANSLATION	14160068.4	Mar 14, 2014		
HM-0179	US	USER INTERFACE FOR ACTIVE DRIVE APPARATUS WITH FINITE RANGE OF MOTION	13/832,895	Mar 15, 2013	9,283,046	Mar 15, 2016
HM-0179C1	US	USER INTERFACE FOR ACTIVE DRIVE APPARATUS WITH FINITE RANGE OF MOTION	15/054,870	Feb 26, 2016		
HM-0180	US	SYSTEM AND METHODS FOR TRACKING ROBOTICALLY CONTROLLED MEDICAL INSTRUMENTS	13/835,698	Mar 15, 2013	9,014,851	Apr 21, 2015
HM-0180C1	US	SYSTEM AND METHODS FOR TRACKING ROBOTICALLY CONTROLLED MEDICAL INSTRUMENTS	14/663,021	Mar 19, 2015	9,710,921	Jul 18, 2017

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HM-0180C2	US	SYSTEM AND METHODS FOR TRACKING ROBOTICALLY CONTROLLED MEDICAL INSTRUMENTS	15/649,522	Jul 13, 2017		
HM-0181	US	USER INPUT DEVICES FOR CONTROLLING MANIPULATION OF GUIDEWIRES AND CATHETERS	13/835,978	Mar 15, 2013		
HM-0182	US	ACTIVE DRIVE MECHANISM WITH FINITE RANGE OF MOTION	13/838,777	Mar 15, 2013	9,408,669	Aug 9, 2016
HM-0182C1	US	ACTIVE DRIVE MECHANISM WITH FINITE RANGE OF MOTION	15/229,639	Aug 5, 2016		
HM-0182EP	EP	ACTIVE DRIVE MECHANISM WITH FINITE RANGE OF MOTION	14160078.3	Mar 14, 2014		
HM-0183C1	US	VASCULAR REMOTE CATHETER MANIPULATOR	15/390,355	Dec 23, 2016		
HM-0185C1	US	LOW FRICTION INSTRUMENT DRIVER INTERFACE FOR ROBOTIC SYSTEMS	15/228,743	Aug 4, 2016		
HM-0191	US	SYSTEMS AND DEVICES FOR CATHETER DRIVING INSTINCTIVENESS	14/666,866	Mar 24, 2015		
HM-0191DE	DE	SYSTEMS AND DEVICES FOR CATHETER DRIVING INSTINCTIVENESS	15160417.0	Mar 23, 2015	EP2923669	Jun 28, 2017
HM-0191EP	EP	SYSTEMS AND DEVICES FOR CATHETER DRIVING INSTINCTIVENESS	15160417.0	Mar 23, 2015	EP2923669	Jun 28, 2017
HM-0191EPD1	EP	SYSTEMS AND DEVICES FOR CATHETER DRIVING INSTINCTIVENESS	17177593.5	Mar 23, 2015		
HM-0191FR	FR	SYSTEMS AND DEVICES FOR CATHETER DRIVING INSTINCTIVENESS	15160417.0	Mar 23, 2015	EP2923669	Jun 28, 2017
HM-0191GB	GB	SYSTEMS AND DEVICES FOR CATHETER DRIVING INSTINCTIVENESS	15160417.0	Mar 23, 2015	EP2923669	Jun 28, 2017

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HM-0193	US	DEVICES, SYSTEMS, AND METHODS FOR CONTROLLING ACTIVE DRIVE SYSTEMS	14/692,499	Apr 21, 2015		
HM-0196	US	ANTI-BUCKLING MECHANISM FOR CATHETERS	14/713,895	May 15, 2015		
HM-0199	US	SYSTEMS AND METHODS FOR ALIGNING AN ELONGATE MEMBER WITH AN ACCESS SITE	14/880,024	Oct 9, 2015		
HM-0200	US	USER INTERFACE FOR MEDICAL ROBOTICS SYSTEM	14/719,034	May 21, 2015		
HM-0206	US	ADAPTIVE CATHETER CONTROL FOR PLANAR USER INTERFACE	15/007,881	Jan 27, 2016		
HM-0207	US	COMPACT HEIGHT TORQUE SENSING ARTICULATION AXIS ASSEMBLY	15/582,390	Apr 28, 2017		
HM-0208	US	ACTIVE DRIVE FOR GUIDEWIRE MANIPULATION	15/250,232	Aug 29, 2016		
HM-0209	US	ROBOT-ASSISTED DRIVING SYSTEMS AND METHODS	15/365,230	Nov 30, 2016		
HM-0211	US	STEERABLE CATHETER WITH SHAFT LOAD DISTRIBUTIONS	15/248,316	Aug 26, 2016		
HM-0212	US	FIBER SHAPE SENSING SYSTEMS AND METHODS	12/837,440	Jul 15, 2010	8,780,339	Jul 15, 2014
HM-0213	US	ROBOTIC INSTRUMENT SYSTEMS AND METHODS UTILIZING OPTICAL FIBER SENSOR	12/192,033	Aug 14, 2008	9,186,046	Nov 17, 2015