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(54) **ULTRASONIC DIAGNOSTIC IMAGING SYSTEM AND CONTROL METHOD THEREOF**

DIAGNOSTISCHES ULTRASCHALL-BILDGEBUNGSSYSTEM UND KONTROLLVERFAHREN
DAFÜR

SYSTEME D'IMAGERIE DIAGNOSTIQUE ULTRASONORE ET SON PROCEDE DE COMMANDE

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Description

TECHNICAL FIELD

[0001] The present invention relates to an ultrasonic diagnostic imaging system and a control method thereof.

BACKGROUND ART

[0002] An ultrasonic diagnostic imaging apparatus (echo) is a diagnostic apparatus that irradiate an examinee with ultrasound, receives ultrasound reflected inside the examinee using a probe and obtains image information from received data. Even when irradiated onto the human body, ultrasound is safe without any particular side effects, and is therefore widely used for diagnostics of various diseases on the medical front lines.

[0003] The ultrasound medical system disclosed in Japanese Patent Application Laid-Open No. 2004-499 discloses a medical system that combines a radiation system for radiological treatment with an ultrasonic diagnostic imaging apparatus. The ultrasonic diagnostic imaging apparatus provides positional information using the position of the radiation apparatus as the origin when providing the position of a tumor to be cured.

[0004] The ultrasound diagnostic apparatus is a simple diagnostic apparatus from the aspect that the ultrasound diagnostic apparatus can acquire image information by only pressing an ultrasonic probe on the human body. A doctor who operates the ultrasound diagnostic apparatus acquires an image by pressing the ultrasonic probe on a patient's body and moving the probe as appropriate. However, since there are many organs in the human body, obtaining image information on an organ to be diagnosed appropriately requires a certain degree of skill in moving the ultrasonic probe.

[0005] Japanese Patent Application Laid-Open No. H01-025576 describes a "scanner of ultrasonic probe." The position, posture and pressure at an end of an ultrasonic probe are measured and the ultrasonic probe is moved and controlled in such a way that the position, posture and pressure are kept constant.

[0006] The method of complementing the skill of the user regarding a scan technique, which is an operation technique, through such control is disclosed.

[0007] The above described method allows the state of the probe with respect to the surface of the human body to be kept adequately. However, keeping the ultrasonic probe in an appropriate state with respect to a region to be inspected in the examinee still requires the operator to have the corresponding skill and knowledge.

[0008] US 6,425,865 B1 discloses a system for medical ultrasound in which an ultrasound probe is positioned by a robot arm under the shared control of an ultrasound operator and a computer. The system comprises a robot arm design suitable for diagnostic ultrasound, a passive or active hand-controller, and a computer system to coordinate the motion and forces of the robot and hand-controller as a function of operator input, sensed parameters and ultrasound images.

[0009] EP 1 348 377 A1 comprises an ultrasonic medical system in which an ultrasonic diagnostic apparatus outputs echo data to a host controller. In the host controller, a tissue coordinate operation unit computes coordinate information of a tumor using a three dimensional probe as an origin; a probe coordinate operation unit computes coordinate information of the three dimensional probe using, as its origin, an X-ray source apparatus which functions as a reference position; and a combined tissue coordinate operation unit uses the coordinate information of the tumor using the three dimensional probe as its origin and the coordinate information of the three dimensional probe using the X-ray source apparatus as its origin to compute coordinate information of the tumor using the X-ray source apparatus as its origin, and outputs the computed coordinate information to the X-ray source apparatus.

[0010] US 2004/0019270 A1 discloses an ultrasonic diagnostic apparatus, ultrasonic probe and navigation method for acquisition of an ultrasonic image. A pre-acquired reference image, a currently picked-up ultrasonic image, and position information indicating a relation between a position of the ultrasonic probe when the reference image was picked-up and a current position of the ultrasonic probe are displayed on a display portion as navigation information. Also, when the following diagnosis image is to be acquired, probe movement information, specifying a position or the like to which the ultrasonic probe has to be moved, is displayed on the display portion as the navigation information.

DISCLOSURE OF THE INVENTION

[0011] In view of the above described problems, it is an object of the present invention to provide an ultrasound diagnostic system and a control method thereof that enables image information on an examinee's tissue to be diagnosed to be appropriately obtained.

[0012] In order to solve the above described problems, one aspect of the present invention is an ultrasonic diagnostic imaging system as set out in independent claim 1.

[0013] Furthermore, another aspect of the present invention is a control method for an ultrasonic diagnostic imaging system as set out in independent claim 6. Other aspects of the present invention are a program as set out in claim 11 and a recording medium as set out in claim 12. Advantageous developments are defined in the dependent claims.

[0014] The present invention adopts a configuration capable of calculating an appropriate position and posture of an ultrasonic probe in an ultrasonic image diagnosis, and can thereby provide a system not depending on an operator who operates the apparatus.

[0015] Other features and advantages of the present invention will be apparent from the following description taken in conjunction with the accompanying drawings, in which like reference characters designate the same or similar parts throughout the figures thereof.

BRIEF DESCRIPTION OF THE DRAWINGS

[0016]

FIG. 1 illustrates a diagnostic method using an ultrasonic diagnostic imaging system according to the present invention.

FIG. 2 is a configuration diagram of the ultrasonic diagnostic imaging system according to the present invention.

FIG. 3 is an outside view of the probe position/posture control apparatus in the present invention.

FIG. 4 is a flowchart illustrating a procedure of the ultrasonic diagnostic imaging system according to the present invention.

FIG. 5 illustrates information stored in the object shape database in the present invention.

FIG. 6 illustrates information stored in the work flow database in the present invention.

FIGS. 7A, 7B, 7C, 7D and 7E illustrate processing by the region detection section in the present invention.

FIG. 8 illustrates a relationship between the ultrasonic probe and an ultrasound image in the present invention.

FIGS. 9A, 9B and 9C illustrate relationships between an ultrasound image and information on the object shape database in the present invention.

FIG. 10 illustrates processing by the coordinate calculation section in the present invention.

FIG. 11 is a configuration diagram of another ultrasonic diagnostic imaging system according to the present invention.

FIGS. 12A and 12B illustrate presentation examples of the guiding information in the present invention.

FIG. 13 is a configuration diagram of a further ultrasonic diagnostic imaging system according to the present invention.

BEST MODES FOR CARRYING OUT THE INVENTION

[0017] Preferred embodiments of the present invention will now be described in detail in accordance with the accompanying drawings.

[0018] Hereinafter, embodiments of an ultrasonic diagnostic imaging apparatus and a control method thereof according to the present invention will be described in detail according to the accompanying drawings. However, the scope of the invention is not limited to the illustrated embodiments.

(First embodiment: Ultrasonic diagnostic imaging system)

[0019] The ultrasonic diagnostic imaging system according to this embodiment is an ultrasonic diagnostic imaging system provided with an ultrasonic probe and an image processing section that converts a signal generated when the ultrasonic probe receives ultrasound reflected from an examinee to image information.

[0020] The system includes the following components.

[0021] More specifically, the system includes a measuring unit (may also be referred to as a "coordinate calculation section" in exemplary embodiments which will be described later) that measures a relative position and relative posture of the ultrasonic probe with respect to the examinee using image information on the examinee acquired by the ultrasonic probe.

[0022] Furthermore, the system also includes a control amount calculation unit that calculates an amount of control of the position and posture of the ultrasonic probe based on the measurement result of the measuring unit.

[0023] The system also includes at least one of a probe control mechanism that controls a position and posture of the ultrasonic probe using the amount of control calculated by the control amount calculation unit and a guiding information presentation unit that presents information for guiding movement of the position and posture of the ultrasonic probe using the amount of control calculated by the control amount calculation unit.

[0024] Here, the measuring unit can measure the relative position and relative posture based on the detection result of the region detection section that detects a specific region of the examinee. The region detection section can detect a region from the correspondence between information on the shape of the region of the examinee and the image information.

[0025] Furthermore, the system can include a database that records the relative position and relative posture between the ultrasonic probe and the examinee beforehand and the control amount calculation unit can calculate the amount of

control using information on the database.

[0026] Here, the information on the relative position and relative posture between the ultrasonic probe and the examinee recorded in the database can be information that records a suitable probe state (position and posture or the like) for carrying out an ultrasonic image diagnosis.

[0027] The ultrasonic probe can have a pressure measuring unit that measures a pressure between the ultrasonic probe and the examinee. In such a case, the database can record information on the pressure between the ultrasonic probe and the examinee.

(Second embodiment: Control method)

[0028] The control method according to this embodiment is a control method for an ultrasonic diagnostic imaging system provided with an ultrasonic probe and an image processing section that converts a signal generated when the ultrasonic probe receives ultrasound reflected from the examinee to image information. More specifically, the method includes the following steps.

- a) A measuring step of measuring a relative position and relative posture of the ultrasonic probe with respect to the examinee using image information on the examinee acquired by the ultrasonic probe
- b) A control amount calculation step of calculating an amount of control of the position and posture of the ultrasonic probe based on the measurement result of the measuring step

[0029] Furthermore, the method includes at least one of e) and f) below.

- e) A probe control step of controlling the position and posture of the ultrasonic probe using the amount of control calculated in the control amount calculation step
- f) A guiding information presentation step of presenting information for guiding movement of the position and posture of the ultrasonic probe using the amount of control calculated by the control amount calculation unit

[0030] Furthermore, it is also an exemplary embodiment that the method includes a region detection step of detecting a specific region of the examinee, and in the measurement step, the relative position and relative posture are measured using the detection result in the region detection step.

[0031] In the region detection step, information on the shape of the examinee is included beforehand and the region can be detected through the correspondence with the image converted by the image processing section.

[0032] The method includes a database that records the relative position and relative posture between the ultrasonic probe and the examinee beforehand, and in the control amount calculation step, the amount of control can be calculated using the information on the database.

[0033] The information on the relative position and relative posture between the ultrasonic probe and the examinee recorded in the database can be information that records a state of the ultrasonic probe for carrying out an ultrasonic image diagnosis.

[0034] The ultrasonic probe may also be provided with a pressure sensor and a pressure measurement step of measuring a pressure between the ultrasonic probe and the examinee can further be added to the steps of the control method. In such a case, the database can record information on the pressure between the ultrasonic probe and the examinee.

[0035] Furthermore, the present invention includes a program to realize the aforementioned control method and a recording medium that records the program to realize the control method.

[0036] Hereinafter, the invention according to the above described embodiments will be described more specifically using exemplary embodiments.

Exemplary Embodiments

(Exemplary Embodiment 1)

A: Overall configuration

[0037] FIG. 1 illustrates an overview of an ultrasonic diagnostic imaging system, which is one of the embodiments of the present invention. The ultrasonic diagnostic imaging system of this exemplary embodiment includes an ultrasonic probe 1001, an ultrasonic diagnostic imaging apparatus 1002, a host controller 1003 and a probe position/posture control apparatus 1004. The ultrasonic probe 1001 is used so as to contact an examinee 1005 such as a human body. Furthermore, the ultrasonic probe 1001 is held by the probe position/posture control apparatus 1004. These apparatuses are

mutually connected and operate by exchanging a control signal or the like through the connection. The probe position/posture control apparatus 1004 is necessary when automating the operation of the ultrasonic probe 1001 and is not indispensable to the aforementioned present invention. The exemplary embodiments which will be described later illustrate the configuration in the case where this probe position/posture control apparatus is not used. FIG. 1 describes the ultrasonic diagnostic imaging apparatus 1002 and the host controller 1003 as separate apparatuses, but it goes without saying that a configuration in which one is incorporated in the other may also be acceptable.

[0038] Next, the function and configuration of the ultrasonic diagnostic imaging system of this exemplary embodiment will be described using FIG. 2.

B: Ultrasound probe

[0039] An ultrasonic probe 2001 is made up of a plurality of wave transmitting/receiving elements 2011 (ultrasonic resonators) that transmit ultrasonic pulses to the examinee 1005 and also receive signals reflected from the examinee.

[0040] The wave transmitting/receiving element 2011 can be made up of a piezoelectric element including a polymer piezoelectric element such as piezoelectric ceramic represented by PZT (lead zirconium titanate) and PVDF (polyvinyl difluoride). In this case, ultrasonic pulses can be generated by converting a time-varying electric signal to mechanical vibration through a piezoelectric element.

[0041] The ultrasonic probe 2001 can be configured by arranging the plurality of wave transmitting/receiving elements 2011 in a one-dimensional array. In this case, the ultrasonic probe 2001 can form a two-dimensional scanning plane in the space and can take cross-sectional images of the examinee. Furthermore, the ultrasonic probe 2001 can be configured by arranging the plurality of wave transmitting/receiving elements 2011 in a two-dimensional array. In this case, the ultrasonic probe 2001 can take images of three-dimensional voxel data of the examinee through three-dimensional and electronic scanning in the space.

C: Ultrasonic diagnostic imaging apparatus

[0042] An ultrasonic diagnostic imaging apparatus 2002 is made up of a transmission beam former 2021, a reception beam former 2022, a signal processing section 2023, a reception memory 2024, an image formation section 2025 and an image display section 2026.

[0043] The transmission beam former 2021 forms ultrasound to be transmitted through the ultrasonic probe 2001 by controlling a transmission drive signal supplied to the plurality of wave transmitting/receiving elements 2011 of the ultrasonic probe 2001.

[0044] The reception beam former 2022 collects received wave data output by the wave transmitting/receiving element 2011 and forms echo data.

[0045] The signal processing section 2023 generates brightness data, blood flow velocity data and displacement data or the like based on the echo data formed by the reception beam former 2022.

[0046] The brightness data, blood flow velocity data and displacement data or the like formed by the signal processing section 2023 are written into the reception memory 2024. The written data is output to a host controller 2003. Furthermore, the data written into the reception memory data 2024 is also output to the image formation section 2025 in the ultrasonic diagnostic imaging apparatus 2002, the image formation section 2025 forms an ultrasound image and the image display section 2026 displays the ultrasound image.

D: Host controller

[0047] The host controller 2003 is made up of an object shape database 2031, a region detection section 2032, a work flow database 2033, a coordinate calculation section (measuring unit) 2034 and a control amount calculation section 2035. However, all or some of the components of the host controller 2003 may also be incorporated in the ultrasonic diagnostic imaging apparatus 2002.

[0048] The object shape database 2031 is a unit that records information such as shape information on the inspection object. For example, data of a standard human body internal structure called a "human body atlas" can be used as the information to be stored in the object shape database.

[0049] The region detection section 2032 references the information stored in the object shape database 2031 and detects a region to be inspected from among ultrasound images input from the ultrasonic diagnostic imaging apparatus 2002. Various detection methods are available. Examples of the detection method include template matching and contour shape matching. More specific processing contents will be described in the procedure which will be described later.

[0050] The work flow database 2033 is a unit that stores information on the ultrasonic probe operation in an ultrasonic image diagnosis. The information to be stored in the work flow database can be, for example, data having information on a relationship of the relative position and posture between an appropriate region and the ultrasonic probe when the

region is imaged using ultrasound for each region to be inspected.

[0051] The coordinate calculation section 2034 calculates the relationship of the relative position and posture between the region to be inspected and the ultrasonic probe 2001 based on the detection result of the region detection section 2032. This calculation can be performed as follows. For example, the relationship between the spatial coordinates relative to the ultrasonic probe 2001 and the image coordinates of the ultrasound image taken by the ultrasonic probe is determined beforehand. Determining the relationship beforehand in this way allows the relationship of the relative position and posture between the region to be inspected and the ultrasonic probe 2001 to be determined from the image coordinates in the ultrasound image of the region to be inspected detected by the region detection section 2032.

[0052] The control amount calculation section 2035 calculates the amount of control on the position and posture of the ultrasonic probe 2001. More specifically, the control amount calculation section 2035 uses information on the ultrasonic probe operation stored in the work flow database 2033 and the relationship of the relative position and posture between the ultrasonic probe 2001 and the region to be inspected calculated by the coordinate calculation section 2034.

E: Probe position/posture control apparatus

[0053] A probe position/posture control apparatus 2004 holds the ultrasonic probe 2001 using a mechanism that can move/rotate the ultrasonic probe 2001 and performs operation to move/rotate the ultrasonic probe 2001 according to the input from the host controller 2003. The probe position/posture control apparatus 2004 can be configured using a base frame 3041, a probe holder 3042 and a plurality of actuators 3043 as shown in FIG. 3 to realize this operation. In this case, the plurality of actuators 3043 are driven according to the input from the host controller 2003. As a result of changing the relationship of the relative position and posture between the base frame 3041 and probe holder 3042, the position and posture of the ultrasonic probe 2001 held by the probe holder 3042 is controlled. Of course, the probe position/posture control apparatus 2004 includes not only an apparatus that controls both the position and posture of the probe but also an apparatus that controls any one of the position and posture.

[0054] FIG. 3 illustrates the mechanism capable of carrying out operation with a total of four degrees of freedom; movement in each axial direction and rotation around each axis on the x-y plane of the base frame 3041 as an example, but in addition to this, a mechanism that also allows movement and rotation with respect to the z axis in the direction perpendicular to x-y can be adopted. This case results in the mechanism capable of carrying out operation with a total of 6 degrees of freedom. Furthermore, a mechanism having any number of degrees of freedom other than 4 and 6 degrees of freedom shown as examples can also be an embodiment of the present invention.

F: Description of processing flow

[0055] Next, a more specific procedure executed by the ultrasonic diagnostic imaging apparatus 2002 according to this embodiment will be described with reference to FIG. 4 and FIG. 2.

f1: Setting of inspection contents (step S100)

[0056] First, the user sets inspection contents as step S100. For example, a plurality of buttons are arranged on an operation panel (not shown) provided on the host controller 2003 and inspection items are assigned to the buttons. Pressing each button allows the corresponding inspection contents to be set. In addition to this, for example, a list of inspection items may be shown on the image display section 2026 of the ultrasonic diagnostic imaging apparatus 2002 so as to allow the user to select an inspection item by operating the operation panel (not shown).

f2: Reading object shape information (shape DB) (step S101)

[0057] Next, the information on the shape of the region to be inspected corresponding to the inspection item set in step S100 is read from the object shape database 2031 into the region detection section 2032. In this case, by recording various types of shape information which vary depending on the attributes such as age, sex, height and weight in the object shape database 2031 and also setting those attributes on the examinee to be inspected, it is possible to read shape information more suited to the examinee.

[0058] This exemplary embodiment will describe a case where "inspection on arterial sclerosis of carotid artery" is set as an inspection item as an example. FIG. 5 shows an example of the information on the shape of the region to be inspected, which is read in this case. In this figure, a region to be inspected 311 shows the shape of the region to be inspected corresponding to the inspection contents set in step S100. Here, the case where the region to be inspected 311 has two-dimensional image information is described as an example, but the present invention is not limited to this and, for example, three-dimensional voxel data or the like may also be used. Furthermore, a reference point 312 is reference information on the position and posture added to the region to be inspected and referenced in the next and

subsequent steps. When reading the above described information recorded in the object shape database 2031, the region detection section 2032 can read the information on the object shape database 2031 in the same format or also read the information after extracting the contour plane and contour lines of the region. Furthermore, information on the contour plane or contour lines of the region to be inspected can also be stored in the shape information database from the beginning.

f3: Reading work flow database (step S102)

[0059] Next, target values of the probe position and posture corresponding to the inspection items set in step S100 are read from the work flow database 2033. FIG. 6 shows an example of target values, which are read in this case. Here, a case where the work flow database stores the range of the relative position of the region to be inspected relative to the reference point and the range of the relative angle as target values of the probe position and posture is shown as an example.

[0060] In this figure, a region to be inspected 331 indicates the region to be inspected set in step S100. A reference point 332 indicates the position which becomes a base point of the target values of the probe position and posture. Furthermore, as indicated by the arrow in the figure, the reference point 332 also has information on the direction to be a reference. A probe target position/target posture 333 indicates the position state and posture state that should be taken by the ultrasonic probe 2001 when an ultrasound image is taken. All these states are read as numerical information using the reference point 332 as a reference.

f4: Image input (step S103)

[0061] Next, an ultrasound image is taken and the image is input. To take an ultrasound image, the transmission beam former 2021 of the ultrasonic diagnostic imaging apparatus 2002 forms and sends an electric signal to drive the wave transmitting/receiving element 2011 of the ultrasonic probe 2001.

[0062] The wave transmitting/receiving element 11 of the ultrasonic probe 2001 receives the ultrasound reflected and returned from within the examinee and the signal is input to the reception beam former 2022 of the ultrasonic diagnostic imaging apparatus 2002. The reception beam former 2022 performs processing such as superimposition on the received signal and inputs the signal to the reception memory 2024. The data input to the reception memory 2024 is displayed on the image display section 2026 through the image formation section 2025 and also input to the region detection section 2032 of the host controller 2003.

f5: Region detection (step S104)

[0063] Next, the region detection section 2032 detects the region to be inspected read from the object shape database 2031 from among the ultrasound images input from the ultrasonic diagnostic imaging apparatus 2002.

[0064] There are various methods of detecting the region to be inspected. Here, a method of applying contour extraction of an object to be imaged to the information on the ultrasound image and region shape database 2031 and detecting the region to be inspected based on matching between the contours will be described using FIGS. 7A, 7B, 7C, 7D and 7E.

[0065] In FIGS. 7A to 7E, FIG. 7A shows an input ultrasound image 7001. Contour information 7002 as shown in FIG. 7B is obtained by applying contour extraction processing to this image. Furthermore, an image 7003 in FIG. 7C is information on the object shape database 2031 and contour information 7004 as shown in FIG. 7D is obtained by applying contour extraction to the image 7003.

[0066] Here, the contour information 7004 in FIG. 7D is superimposed on the contour information 7002 in FIG. 7B and the amount of movement/amount of rotation of FIG. 7D that corresponds to the maximum superimposition between the two pieces of information is searched (of course, the amount of movement/amount of rotation of the image FIG. 7B may also be searched).

[0067] As a result, the amount of movement/amount of rotation corresponding to the maximum superimposition can be calculated as shown in 7005 in FIG. 7E. Here, the image 7006 corresponds to the image 7004 in FIG. 7D and the image 7007 corresponds to the image 7002 in FIG. 7B. Here, the procedure for detecting a region by applying contour extraction processing to both pieces of information on the ultrasound image and the region shape database and comparing the two contour shapes has been described.

[0068] However, the procedure for region detection in step S104 is not limited to this method.

[0069] For example, there can also be a procedure that detects a plurality of characteristic corners instead of carrying out contour extraction processing and detects the region through matching among those characteristic corners. Furthermore, there can also be a procedure for detecting the region by directly comparing pixel values between the ultrasound image and the object shape database 2031. In this case, the similarity among pixel values can be evaluated by indices such as correlation coefficients and mutual information content. Furthermore, more robust region detection can also be

performed in consideration of deformation of the shape of the region.

[0070] With the above described procedure, the region similar to the shape information stored in the object shape database 2031 can be detected from the ultrasound image. Furthermore, the detection intensity using the similarity of both shapes as a reference and a relationship between positions where both shapes closely resemble each other can also be obtained simultaneously.

[0071] Here, the case where both the ultrasound image and the shape information stored in the object shape database 2031 are two-dimensional image data has been described, but the present invention is not limited to this. For example, at least one of the ultrasound image and the shape information stored in the object shape database 2031 may be three-dimensional voxel data. In such a case, the target region can be detected through matching between three-dimensional voxel data or matching between two-dimensional image data and three-dimensional voxel data.

f6: Determining detection result (step S105)

[0072] In step S105, it is determined whether or not the region has been detected based on the result of the region detection carried out in step S104.

[0073] This determination can be made assuming, for example, that when the maximum value of the detection intensity obtained as a result of the region detection is greater than a preset threshold, the region to be inspected has been detected, whereas when smaller than the threshold, the region to be inspected has not been detected. In addition to this, when the detection intensity exceeds the threshold for several frames consecutively, it is also possible to determine that the region has been detected. In this case, there is an advantage that a determination can be made with higher reliability. Furthermore, a value that differs from one region to be inspected to another can also be set as the threshold. In this case, an appropriate threshold can be set in consideration of the difference between regions with and without large individual differences in shape.

[0074] When it is determined in step S105 that the region to be inspected has been detected, the process moves to step S107 or moves to step S106 otherwise. f7: Calculating amount of region search control (step S106)

[0075] In step S105, when the region to be inspected has not been detected from among the ultrasound images, control over the movement/rotation is performed so as to change the position and posture of the ultrasonic probe 2001 so that the inspection object falls within the imaging range. In this case, the simplest method for moving/rotating the ultrasonic probe 2001 may be the method of thoroughly scanning the movable range of the probe position/posture control apparatus 2004. For example, the ultrasonic probe 2001 is moved to the position of the farthest end of the probe position/posture control apparatus 2004 and a control signal is sent to the probe position/posture control apparatus so as to gradually move the ultrasonic probe 2001 while taking ultrasound images. If the region to be inspected is detected in the process, scanning of the position and posture of the ultrasonic probe is finished according to the determination result in step S105 and the process moves to step S107:

[0076] Furthermore, as another method, not only the region to be inspected but also the shapes of regions existing around and their relative positional relationship with the region to be inspected can be stored in the region shape database. Such storage allows the ultrasonic probe 1 to be moved or rotated according to the detection results of the peripheral regions even when the region to be inspected cannot be directly detected.

[0077] The more specific operation of the probe position/posture control apparatus 2004 will be described in detail in the description of step S111.

f8: Coordinate calculation (step S107)

[0078] Next, the coordinate calculation section 2034 (FIG. 2) calculates the relative position and posture between the ultrasonic probe 2001 and a reference point in the object shape database 2031.

[0079] This calculation is performed based on the following first and second relationships. The first relationship is a relationship between the spatial coordinates using the ultrasonic probe 2001 as a reference and the image coordinates of the ultrasound image taken. The second relationship is a correlation between the position and posture information on the image of the region to be inspected detected in step S104 and the reference coordinates stored in the object shape database 2031.

[0080] This processing will be described in detail using FIG. 8 and FIGS. 9A, 9B and 9C.

[0081] For simplicity of description here, suppose that all the real space, ultrasound image and shape information of the object shape database 2031 occupy a two-dimensional space. However, the present invention is not limited to this and when, for example, all or part of the information occupies a three-dimensional space, the present invention can be implemented by a simple extension in the following description.

[0082] FIG. 8 illustrates a relationship between coordinates of the real space in which an imaging object exists and those of an ultrasound image generated through ultrasonic imaging. Reference numeral 8001 schematically denotes an ultrasonic probe, 8002 denotes ultrasound, 8003 denotes a host controller and 8000 denotes a measurement target.

[0083] In this figure, coordinates on an image are expressed by vector $i = (u \ v)^t$, coordinates in the real space are expressed by vector $r = (x \ y)^t$. Here, "t" added at the shoulder of the vector represents transposition. Suppose the coordinate vector i represents a pixel point on an image located at the u th position in the rightward direction and v th position in the downward direction on the screen relative to the origin assuming the left top end point of the image as the origin $(0 \ 0)^t$. Furthermore, the coordinate vector r has the origin $(0 \ 0)$ inside the ultrasonic probe 8001 and expresses a point in the real space which is moved by x [mm] and y [mm] respectively relative to the origin with respect to two mutually orthogonal axes that form an imaging plane.

[0084] The ultrasonic diagnostic imaging apparatus 2002 (FIG. 2) generates ultrasound from the ultrasonic probe 2001 (FIG. 1) and determines a brightness value at a point i on the ultrasound image based on the observed value of the reflected signal from a point r in the real space. Here, the correspondence between the point r in the real space and point i on the ultrasound image is expressed by the following expression using a function T_{ri} .

$$i = T_{ri} (r) \quad (\text{Expression 1})$$

[0085] Here, assuming that the coordinate vector i has a linear relationship with respect to the coordinate vector r , i can be expressed as:

$$i = T_{ri} r \quad (\text{Expression 2})$$

where T_{ri} represents a matrix expressing the linear relationship between i and r , and i and r are redefined as extended vectors $i = (u \ v \ 1)^t$ and $r = (x \ y \ 1)^t$ respectively. Normally, the assumption of the above described linear relationship sufficiently holds in a calibrated ultrasonic diagnostic imaging apparatus. Furthermore, on the contrary, transformation from the point i on the image to the point r in the real space can be expressed using an inverse matrix T_{ri}^{-1} of the matrix T_{ri} as:

$$r = T_{ri}^{-1} i \quad (\text{Expression 3})$$

Since the matrix T_{ri} is a regular matrix except special cases, the inverse matrix T_{ri}^{-1} can be calculated.

[0086] On the other hand, the correspondence between the point i on the ultrasound image and the point of the object shape database 2031 is obtained from the processing result in step S104. This will be described using FIGS. 9A, 9B and 9C. 9000 and 9001 in FIG. 9A correspond to 7006 and 7007 in FIGS. 7A, 7B, 7C, 7D and 7E respectively. First, suppose the point in the object shape database 2031 with respect to the point i on the ultrasound image is vector $m = (u' \ v' \ 1)^t$. On the assumption that vector m (FIG. 9B 9010) and vector i (FIG. 9C 9020) have a linear relationship, i can be expressed using a linear transformation matrix T_{mi} as:

$$i = T_{mi} m \quad (\text{Expression 4})$$

[0087] Furthermore, the relationship with the point r in the real space corresponding to an arbitrary point m in the object shape database 2031 can be expressed using Expression 3 and Expression 4 as:

$$r = T_{ri}^{-1} T_{mi} m \quad (\text{Expression 5})$$

Here, assuming that the point m represents coordinates of a region reference point of the object shape database 2031, the corresponding point in the real space can be determined as a coordinate r using the ultrasonic probe 2001 as a reference.

[0088] Here, the example has been described where the position of the region reference point of the object shape database 2031 is determined in a coordinate system using the ultrasonic probe 2001 as a reference, but to the contrary, the position and posture of the ultrasonic probe may also be determined using the region reference point of the object shape database 2031 as a reference.

f9: Calculating difference from target (step S108)

[0089] As the next step, the coordinate calculation section 2034 further calculates a correspondence between the position and posture of the ultrasonic probe 2001 and the target position and posture read from the work flow database 2033. To calculate this correspondence, a correspondence between the position and posture of the reference point of the region to be inspected in the coordinate system using the ultrasonic probe 2001 obtained in step S107 as a reference and the target position and posture of the work flow database 2033 is determined. This processing will be described in detail using FIG. 10.

[0090] FIG. 10 illustrates the target position and posture of the ultrasonic probe stored in the work flow database and the current position and posture of the ultrasonic probe. Here, a region to be inspected 351, a reference point 352, a probe target position and posture 353 are the information read in step S102. Furthermore, the region to be inspected 351 and reference point 352 can be assumed to express the same contents as the region to be inspected 311 and reference point 312 out of the information stored in the region shape database 2031 read in step S101.

[0091] In FIG. 10, the probe target position and posture 353 means the target values of the position and posture of the probe in the coordinate system whose origin is the reference point 352 of the region to be inspected. Here, the probe target position and posture 353 are divided into components of translational motion and rotation, and expressed as g_t and g_{ang} respectively. Similarly, the probe current position and posture 354 can also be expressed as p_t and p_{ang} respectively based on the relative position and posture with respect to the reference point of the ultrasonic probe and region to be inspected already determined in S107. From the information, the difference in position δ_t between the current ultrasonic probe and the target, and difference in posture δ_{ang} can be calculated from the following expressions respectively.

$$\delta_t = p_t - g_t \quad (\text{Expression 6})$$

$$\delta_{ang} = p_{ang} - g_{ang} \quad (\text{Expression 7})$$

Through the above described processing, the degree of deviation in position/angle of the ultrasonic probe 2001 from the target position and posture at the present moment can be calculated.

f11: Determining reach of target (step S109)

[0092] Next, it is determined whether or not the ultrasonic probe has reached the target position and posture based on the relative difference of the current position and posture of the ultrasonic probe from the target value calculated in step S108. As the method for determining this, the ultrasonic probe may be determined as having reached the target when the difference between the current position/posture of the ultrasonic probe 1 calculated in step S108 and the target value is smaller than a predetermined threshold and determined as not having reached the target otherwise.

[0093] Furthermore, a value that varies depending on the setting of the region to be inspected may also be automatically set for this threshold. In this case, the target range of the position/posture of the ultrasonic probe can be changed for each inspection object.

f12: Calculating amount of target direction control (step S110)

[0094] When the determination result in step S109 shows that the probe position/posture falls short of the target value, step S110 is carried out. In step S110, the control amount calculation section 2035 calculates the amount of control to be sent to the probe position/posture control apparatus so as to make the probe position/posture closer to the target value. Calculation of the amount of control can take various modes depending on the characteristic of the control apparatus. When, for example, the direction of movement/rotation is specified for the probe position/posture control apparatus and constant-speed drive is performed, the direction can be determined based on the positive/negative sign of each component value of the position difference δ_t and the posture difference δ_{ang} from the target value calculated in step S108.

[0095] As another method, the amount of control can also be calculated using both the signs and absolute values of the differences δ_t and δ_{ang} from the target value. In this case, there can be a method of determining the direction of control based on, for example, the signs of the difference values and determining the speed based on the absolute values. f13: Probe movement/rotation control (step S111)

[0096] In step S111, the amount of control calculated in step S106 or step S110 is input to the ultrasonic probe position/posture control apparatus 2004 (FIG. 2) and the position and posture of the ultrasonic probe are driven so as to approximate to the target values. For example, based on the amount of control over the position and posture of the probe calculated in step S110, a voltage proportional, for example, to the amount of control is applied to the corresponding actuators 3043 (FIG. 3). In this way, the actuators 3043 are driven in the direction approximating to the target position and posture recorded in the work flow database 2033, and as a result, the ultrasonic probe 2001 held approximates to the target state.

[0097] Performing the processing from step S100 to step S111 described above can keep the ultrasonic probe 2001 in an appropriate position and posture with respect to the region to be inspected. By so doing, it is possible to provide an ultrasonic diagnostic imaging apparatus that allows even a user who has not special skill about ultrasonic imaging to take an ultrasound image suitable for a diagnosis.

[0098] This exemplary embodiment has described the case where the probe position/posture control apparatus 2004 mechanically moves/rotates the position and posture of the ultrasonic probe 2001 to realize ultrasonic imaging of a region to be inspected from the appropriate position/angle as an example. However, the embodiment of the present invention is not limited to this. When, for example, an ultrasonic probe having a plurality of wave transmitters/receivers capable of electronically changing the position/direction of transmission/reception of an ultrasound signal is used, making the wave transmission/reception position and direction of the ultrasound signal the control targets can produce the effects similar to those of the above described embodiment. Moreover, a configuration combining both mechanical control and electronic control also becomes one embodiment of the present invention.

(Exemplary Embodiment 2)

[0099] Exemplary Embodiment 1 has described the example where the ultrasonic probe is moved/rotated so as to guide the ultrasonic probe to an appropriate position and posture with respect to an object of ultrasound inspection, but the embodiment of the present invention is not limited to this.

[0100] For example, there can also be an embodiment of presenting navigation to urge the user to move/rotate the ultrasonic probe instead of providing an apparatus for moving/rotating the ultrasonic probe. An example of adopting such an embodiment will be described.

A: Overall configuration

[0101] FIG. 11 illustrates the configuration of the exemplary embodiment presenting navigation to move/rotate the ultrasonic probe to the user.

[0102] The ultrasonic diagnostic imaging system of this embodiment is made up of an ultrasonic probe 2906, an ultrasonic diagnostic imaging apparatus 2907 and a host controller 2908.

B: Ultrasound probe

[0103] Since the ultrasonic probe 2906 is similar to that in Exemplary Embodiment 1, descriptions thereof will be omitted.

C: Ultrasonic diagnostic imaging apparatus

[0104] The ultrasonic diagnostic imaging apparatus 2907 is made up of a transmission beam former 2971, a reception beam former 2972, a signal processing section 2973, a reception memory 2974, an image formation section 2975 and an image display section 2976.

[0105] The image display section 2976 presents ultrasound image and navigation information based on signals from the image formation section 2975 and host controller 2908. Since the rest of the configuration included in the ultrasonic diagnostic imaging apparatus 2907 is similar to that described in Exemplary Embodiment 1, descriptions thereof will be omitted.

D: Host controller

[0106] The host controller 2908 is made up of an object shape database 2981, a region detection section 2982, a work flow database 2983, a coordinate calculation section 2984 and a guiding information generation section 2985.

[0107] However, all or some of the components of the host controller 2908 can also be incorporated in the ultrasonic diagnostic imaging apparatus 2907. The guiding information generation section 2985 generates guiding information on the movement/rotation of the probe to be carried out by the user based on the difference from the target value of the probe calculated by the coordinate calculation section 2984. The guiding information generated is sent to the image

display section 2976 of the ultrasonic diagnostic imaging apparatus 2907 and presented to the user using a display or the like.

The rest of the configuration included in the host controller 2908 is the same as that described in Exemplary Embodiment 1, and therefore descriptions thereof will be omitted.

E: Guiding information generation section

[0108] The guiding information generated by the guiding information generation section 2985 and presented by the image display section 2976 can be presented using symbols like an arrow as shown, for example, in FIG. 12A. Furthermore, as shown in FIG. 12B, the image display section 2976 may be enabled to present an ultrasound image and present guiding information simultaneously.

[0109] Furthermore, the presentation of the guiding information is not limited to the presentation by the image display section 2976 of the ultrasonic diagnostic imaging apparatus 2907. For example, the ultrasonic probe 2906 may be newly provided with a display section for presenting guiding information on the position and posture to enable guiding information to be presented. In this case, the user has the merit of being able to intuitively recognize the probe moving direction without referencing the ultrasonic diagnostic imaging apparatus 2907.

[0110] Furthermore, the guiding information of this exemplary embodiment is not limited to presentation with an image. As another configuration example, the host controller 2908 or ultrasonic diagnostic imaging apparatus 2907 or ultrasonic probe 2906 may be newly provided with a sound presentation section such as a speaker and the navigation generation section 2985 may be enabled to create guiding information with speech. In this case, the user can obtain the guiding information without viewing the screen.

(Exemplary Embodiment 3)

[0111] Exemplary Embodiment 1 and Exemplary Embodiment 2 have described the case where the host controller includes the database that stores information on the region to be inspected and the ultrasound inspection work flow as an example. However, the present invention is not limited to this embodiment.

[0112] Exemplary Embodiment 3 will describe an example of an ultrasound diagnostic system that acquires information on the region to be inspected and the ultrasound inspection work flow with reference to an external database.

[0113] FIG. 13 is a configuration diagram of an ultrasonic diagnostic imaging system according to this exemplary embodiment that acquires information from an external database via a network. The ultrasonic diagnostic imaging system according to this exemplary embodiment is made up of the following components. More specifically, the ultrasonic diagnostic imaging system is made up of an ultrasonic probe 3991, an ultrasonic diagnostic imaging apparatus 3992, a host controller 3993, a probe position/posture control apparatus 3994, an object shape database 3996 and a work flow database 3997.

[0114] Furthermore, the host controller 3993 is connected to the object shape database 3996 and the work flow database 3997 via a network 3995.

[0115] Here, a case where both the object shape database 3996 and work flow database 3997 are connected to the host controller 3993 via the network is described as an example, but the embodiment of the present invention is not limited to this.

[0116] For example, such a configuration may also be adopted that only one of the object shape database 3996 and the work flow database 3997 is connected via the network and the other is located inside the host controller 3993. Moreover, a connection via the network 3995 is shown as an example of connection, but the mode of connection may also be a so-called LAN connection or other connection modes such as USB connection, serial connection or parallel connection. Furthermore, the object shape database 3996 or work flow database 3997 and host controller 3993 need not always be paired. For example, depending on the embodiment, such a mode may also be adopted that the host controllers 3993 of a plurality of ultrasonic diagnostic imaging systems share the object shape database 3996 or the work flow database 3997.

[0117] Adopting the above described configuration eliminates the necessity for the ultrasound diagnostic system of the present invention to store necessary region shape information or work flow information in the host controller 3993 and enables a database supplied to the system to be flexibly expanded or changed.

[0118] Moreover, the host controller may also be configured so that the information stored in the object shape database 3996 and work flow database 3997 can be added, changed or deleted through an external operation. In this case, it is possible to flexibly update the database associated with expansion of the corresponding inspection items and revision of the inspection method or the like.

(Other embodiments)

[0119] Furthermore, it goes without saying that the object of the present invention can also be attained by supplying a recording medium that records software program code to realize the functions of the aforementioned embodiments and exemplary embodiments to the system or apparatus. More specifically, a computer (or CPU or MPU) of the system or the apparatus reads and executes the program code stored in the recording medium. In this case, the program code itself read from the recording medium realizes the functions of the aforementioned embodiments and the recording medium storing the program code constitutes the present invention.

[0120] The functions of the aforementioned embodiments are realized by the computer executing the read program code, but the present invention does not include only such a case. It goes without saying that the present invention also includes a case where based on instructions of the program code, the operating system (OS) operating on the computer performs part or whole of actual processing and realizes the functions of the aforementioned embodiments.

[0121] Furthermore, it goes without saying that the present invention also includes a case where the functions of the aforementioned embodiments are realized through the processing performed in A) and B) below.

A) The program code read from the recording medium is written into a memory provided for a feature expansion card inserted in the computer or a feature expansion unit connected to the computer.

B) Based on instructions of the program code, a CPU provided for the feature expansion card or feature expansion unit then performs part or whole of the actual processing.

[0122] When the present invention is applied to the above described recording medium, the recording medium stores the program code corresponding to the flowchart described above.

[0123] The descriptions in the aforementioned embodiments are only examples of the preferred ultrasonic diagnostic imaging apparatus according to the present invention and the present invention is not limited to these examples.

[0124] The present invention is not limited to the above embodiments and various changes and modifications can be made within the spirit and scope of the present invention. Therefore to apprise the public of the scope of the present invention, the following claims are made.

Claims

1. An ultrasonic diagnostic imaging system provided with an ultrasonic probe (1001) and an image processing section (2023) that converts a signal generated when the ultrasonic probe receives ultrasound reflected from an examinee (1005) to image information, comprising:

a measuring unit (2034) that measures a relative position and a relative posture of the ultrasonic probe with respect to the examinee using image information on the examinee acquired by the ultrasonic probe;
a control amount calculation unit (2035) that calculates an amount of control of the position and posture of the ultrasonic probe based on the measurement result of the measuring unit; and
at least one of a probe control mechanism (2004) that controls a position and posture of the ultrasonic probe using the amount of control calculated by the control amount calculation unit and a guiding information presentation unit (2985, 2976) that presents information for guiding movement of the position and posture of the ultrasonic probe using the amount of control calculated by the control amount calculation unit,

characterized in that

a plurality of buttons or a list of inspection items shown on an image display are provided to set an inspection item; a shape obtaining unit (2032) is provided to obtain, from a database (2031) that stores shape information on the shape of an object to be inspected for each inspection item, the shape information corresponding to the inspection item set by the setting unit (2003), and
the measuring unit is configured to measure the relative position and the relative posture based on the detection result of a region detection section (2032) that is configured to detect the object to be inspected based on the shape information obtained by the shape obtaining unit (2032) in the image information acquired by the ultrasonic probe (1001).

2. The ultrasonic diagnostic imaging system according to claim 1, wherein:

a target position obtaining unit (2032) is provided to obtain, from a second database (2033) that stores a target position and posture of the ultrasonic probe (1001) with respect to the object to be inspected for each inspection item, the target position and posture of the ultrasonic probe corresponding to the inspection item set by the

setting unit (2003),

the measuring unit (2034) is configured to calculate a correspondence between the obtained target position and posture and the position and posture of the ultrasonic probe, and

the control amount calculation unit (2035) is configured to calculate (S110) the amount of control of the position and posture of the ultrasonic probe to be sent to the probe control mechanism (2004) so as to make the position and posture of the ultrasonic probe closer to the obtained target position when the ultrasonic probe has not reached the obtained target position.

3. The ultrasonic diagnostic imaging system according to claim 2, wherein:

the ultrasonic probe is controlled to reach the obtained target position (S110 to S111); and

a probe control mechanism (2004) is provided to change (S106) the position and posture of the ultrasonic probe so that the object to be inspected falls within an imaging range if the region detection unit (2032) cannot detect the object to be inspected.

4. The ultrasonic diagnostic imaging system according to any one of claims 1 to 3, wherein the ultrasonic probe (1001) comprises a pressure measuring unit that measures a pressure between the ultrasonic probe and the examinee (1005).

5. The ultrasonic diagnostic imaging system according to any one of claims 1 to 4, wherein the database (2031, 2033) records information on a pressure between the ultrasonic probe (1001) and the examinee (1005).

6. A control method for an ultrasonic diagnostic imaging system provided with an ultrasonic probe (1001) and an image processing section (2023) that converts a signal generated when the ultrasonic probe receives ultrasound reflected from an examinee (1005) to image information, comprising:

a measuring step of measuring a relative position and relative posture of the ultrasonic probe with respect to the examinee using image information on the examinee acquired by the ultrasonic probe;

a control amount calculation step of calculating an amount of control of a position and posture of the ultrasonic probe based on the measurement result; and

at least one of a probe control step of controlling the position and posture of the ultrasonic probe by a probe control mechanism (2004) using the calculated amount of control and a guiding information presentation step of presenting information for guiding movement of the position and posture of the ultrasonic probe using the amount of control calculated by the control amount calculation unit,

characterized by

a setting step of setting an inspection item;

a shape obtaining step of obtaining, from a database (2031) that stores shape information on the shape of an object to be inspected for each inspection item, the shape information corresponding to the inspection item set in the setting step; wherein

the measuring step measures the relative position and the relative posture based on the detection result of a region detection step of detecting the object to be inspected based on the shape information obtained in the shape obtaining step in the image information acquired by the ultrasonic probe (1001).

7. The control method according to claim 6, further comprising:

a target position obtaining step of obtaining, from a second database (2033) that stores a target position and posture of the ultrasonic probe (1001) with respect to the object to be inspected for each inspection item, the target position and posture of the ultrasonic probe corresponding to the inspection item set in the setting step, wherein

the measuring step calculates a correspondence between the obtained target position and posture and the position and posture of the ultrasonic probe, and

the control amount calculation step calculates (S110) the amount of control of the position and posture of the ultrasonic probe to be sent to the probe control mechanism (2004) so as to make the position and posture of the ultrasonic probe closer to the obtained target position when the ultrasonic probe has not reached the obtained target position.

8. The control method according to claim 7, wherein

the ultrasonic probe is controlled to reach the obtained target position (S110 to S111); and

the control method further comprises:

a probe control step of changing (S106) the position and posture of the ultrasonic probe so that the object to be inspected falls within an imaging range if the region detection step cannot detect the object to be inspected.

9. The control method according to any one of claims 6 to 8, further comprising a pressure measuring step of the ultrasonic probe measuring a pressure between the ultrasonic probe and the examinee (1005).
10. The control method according to any one of claims 6 to 9, further comprising a recording step of the database recording information on the pressure between the ultrasonic probe (1001) and the examinee (1005).
11. A program for implementing the control method according to any one of claims 6 to 10.
12. A recording medium that records a program for implementing the control method according to any one of claims 6 to 10.

Patentansprüche

1. Diagnostisches Ultraschall-Bildgebungssystem, das mit einer Ultraschallsonde (1001) und einem Bildverarbeitungsabschnitt (2023) versehen ist, der ein Signal in Bildinformation konvertiert, das generiert wird, wenn die Ultraschallsonde von einem Prüfling (1005) reflektierten Ultraschall empfängt, mit:

einer Messeinheit (2034), die eine relative Position und eine relative Lage der Ultraschallsonde bezogen auf den Prüfling unter Verwendung von durch die Ultraschallsonde gewonnener Bildinformation über den Prüfling misst;

einer Steuerungsausmaßberechnungseinheit (2035), die ein Ausmaß einer Steuerung der Position und Lage der Ultraschallsonde basierend auf dem Messergebnis der Messeinheit berechnet; und
zumindest einem aus einem Sondensteuerungsmechanismus (2004), der eine Position und Lage der Ultraschallsonde unter Verwendung des durch die Steuerungsausmaßberechnungseinheit berechneten Steuerungsausmaßes steuert, und einer Führungsinformationsdarstellungseinheit (2985, 2976), die Informationen zur Bewegungsführung der Position und Lage der Ultraschallsonde unter Verwendung des durch die Steuerungsausmaßberechnungseinheit berechneten Steuerungsausmaßes darstellt,

dadurch gekennzeichnet, dass

eine Vielzahl von Tasten oder eine auf einer Bildanzeige gezeigte Liste von Untersuchungselementen bereitgestellt sind, um ein Untersuchungselement einzustellen;

eine Formbeschaffungseinheit (2032) bereitgestellt ist, um aus einer Datenbank (2031), in der Forminformationen über die Form eines zu untersuchenden Objekts für jedes Untersuchungselement gespeichert sind, die dem durch die Einstelleinheit (2003) eingestellten Untersuchungselement entsprechenden Forminformationen zu beschaffen, und

die Messeinheit dazu eingerichtet ist, um die relative Position und die relative Lage basierend auf dem Erfassungsergebnis eines Bereichserfassungsabschnitts (2032) zu messen, der dazu eingerichtet ist, um das zu untersuchende Objekt basierend auf den durch die Formbeschaffungseinheit (2032) beschafften Forminformationen in der durch die Ultraschallsonde (1001) gewonnenen Bildinformation zu erfassen.

2. Diagnostisches Ultraschall-Bildgebungssystem gemäß Anspruch 1, wobei:

eine Zielpositionsbeschaffungseinheit (2032) dazu bereitgestellt ist, um aus einer zweiten Datenbank (2033), in der eine Zielposition und -lage der Ultraschallsonde (1001) bezogen auf das zu untersuchende Objekt für jedes Untersuchungselement gespeichert sind, die dem durch die Einstelleinheit (2003) eingestellten Untersuchungselement entsprechende Zielposition und -lage der Ultraschallsonde zu beschaffen, die Messeinheit (2034) dazu eingerichtet ist, um eine Entsprechung zwischen der beschafften Zielposition und -lage und der Position und Lage der Ultraschallsonde zu berechnen, und die Steuerungsausmaßberechnungseinheit (2035) dazu eingerichtet ist, um das zu dem Sondensteuerungsmechanismus (2004) zu sendende Ausmaß einer Steuerung der Position und Lage der Ultraschallsonde zu berechnen (S110), um die Position und Lage der Ultraschallsonde an die beschaffte Zielposition anzunähern, wenn die Ultraschallsonde die beschaffte Zielposition nicht erreicht hat.

3. Diagnostisches Ultraschall-Bildgebungssystem gemäß Anspruch 2, wobei:

die Ultraschallsonde gesteuert wird, um die beschaffte Zielposition zu erreichen (S110 bis S111); und ein Sondensteuerungsmechanismus (2004) bereitgestellt ist, um die Position und Lage der Ultraschallsonde derart zu ändern (S106), dass das zu untersuchende Objekt innerhalb eines Bereichs einer Bildgebung fällt, wenn die Bereichserfassungseinheit (2032) das zu untersuchende Objekt nicht erfassen kann.

4. Diagnostisches Ultraschall-Bildgebungssystem gemäß einem der Ansprüche 1 bis 3, wobei die Ultraschallsonde (1001) eine Druckmesseinheit aufweist, die einen Druck zwischen der Ultraschallsonde und dem Prüfling (1005) misst.

5. Diagnostisches Ultraschall-Bildgebungssystem gemäß einem der Ansprüche 1 bis 4, wobei in der Datenbank (2031, 2033) Informationen über einen Druck zwischen der Ultraschallsonde (1001) und dem Prüfling (1005) aufgezeichnet sind.

6. Steuerungsverfahren für ein diagnostisches Ultraschall-Bildgebungssystem, das mit einer Ultraschallsonde (1001) und einem Bildverarbeitungsabschnitt (2023) versehen ist, der ein Signal in Bildinformation konvertiert, das generiert wird, wenn die Ultraschallsonde von einem Prüfling (1005) reflektierten Ultraschall empfängt, mit:

einem Messschritt, um eine relative Position und eine relative Lage der Ultraschallsonde bezogen auf den Prüfling unter Verwendung von durch die Ultraschallsonde gewonnener Bildinformation über den Prüfling zu messen;

einem Steuerungsausmaßberechnungsschritt, um ein Ausmaß einer Steuerung einer Position und Lage der Ultraschallsonde basierend auf dem Messergebnis zu berechnen; und

zumindest einem aus einem Sondensteuerungsschritt, um die Position und Lage der Ultraschallsonde mittels eines Sondensteuerungsmechanismus (2004) unter Verwendung des berechneten Steuerungsausmaßes zu steuern, und einem Führungsinformationsdarstellungsschritt, um Informationen zur Bewegungsführung der Position und Lage der Ultraschallsonde unter Verwendung des durch die Steuerungsausmaßberechnungseinheit berechneten Steuerungsausmaßes darzustellen,

gekennzeichnet durch

einen Einstellschritt, um ein Untersuchungselement einzustellen;

einen Formbeschaffungsschritt, um aus einer Datenbank (2031), in der Forminformationen über die Form eines zu untersuchenden Objekts für jedes Untersuchungselement gespeichert sind, die dem in dem Einstellschritt eingestellten Untersuchungselement entsprechenden Forminformationen zu beschaffen, wobei

in dem Messschritt die relative Position und die relative Lage basierend auf dem Erfassungsergebnis eines Bereichserfassungsschrittes, um das zu untersuchende Objekt basierend auf den in dem Formbeschaffungsschritt beschafften Forminformationen in der **durch** die Ultraschallsonde (1001) gewonnenen Bildinformation zu erfassen, gemessen wird.

7. Steuerungsverfahren gemäß Anspruch 6, ferner mit:

einem Zielpositionbeschaffungsschritt, um aus einer zweiten Datenbank (2033), in der eine Zielposition und -lage der Ultraschallsonde (1001) bezogen auf das zu untersuchende Objekt für jedes Untersuchungselement gespeichert sind, die dem in dem Einstellschritt eingestellten Untersuchungselement entsprechende Zielposition und -lage der Ultraschallsonde zu beschaffen, wobei

in dem Messschritt eine Entsprechung zwischen der beschafften Zielposition und -lage und der Position und Lage der Ultraschallsonde berechnet wird, und

in dem Steuerungsausmaßberechnungsschritt das zu dem Sondensteuerungsmechanismus (2004) zu sendende Ausmaß einer Steuerung der Position und Lage der Ultraschallsonde berechnet wird (S110), um die Position und Lage der Ultraschallsonde an die beschaffte Zielposition anzunähern, wenn die Ultraschallsonde die beschaffte Zielposition nicht erreicht hat.

8. Steuerungsverfahren gemäß Anspruch 7, wobei:

die Ultraschallsonde gesteuert wird, um die beschaffte Zielposition zu erreichen (S110 bis S111); und das Steuerungsverfahren ferner aufweist:

einen Sondensteuerungsschritt, um die Position und Lage der Ultraschallsonde derart zu ändern (S106),

dass das zu untersuchende Objekt innerhalb eines Bereichs einer Bildgebung fällt, wenn in dem Bereichserfassungsschritt das zu untersuchende Objekt nicht erfasst werden kann.

9. Steuerungsverfahren gemäß einem der Ansprüche 6 bis 8, ferner mit einem Druckmessschritt der Ultraschallsonde, um einen Druck zwischen der Ultraschallsonde und dem Prüfling (1005) zu messen.
10. Steuerungsverfahren gemäß einem der Ansprüche 6 bis 9, ferner mit einem Aufzeichnungsschritt der Datenbank, um Informationen über den Druck zwischen der Ultraschallsonde (1001) und dem Prüfling (1005) aufzuzeichnen.
11. Programm für eine Implementierung des Steuerungsverfahrens gemäß einem der Ansprüche 6 bis 10.
12. Aufzeichnungsmedium, das ein Programm für eine Implementierung des Steuerungsverfahrens gemäß einem der Ansprüche 6 bis 10 aufzeichnet.

Revendications

1. Système d'imagerie de diagnostic aux ultrasons pourvu d'une sonde à ultrasons (1001) et d'une section (2023) de traitement d'image qui convertit, en information d'image, un signal engendré lorsque la sonde à ultrasons reçoit des ultrasons réfléchis par un sujet examiné (1005), comprenant :

une unité (2034) de mesure qui mesure la position relative et la posture relative de la sonde à ultrasons par rapport au sujet examiné en utilisant l'information d'image du sujet examiné acquise par la sonde à ultrasons ;
une unité (2035) de calcul de valeur de commande qui calcule, en se basant sur le résultat de mesure de l'unité de mesure, une valeur de commande des position et posture de la sonde à ultrasons ; et

au moins l'un d'un mécanisme (2004) de commande de sonde qui commande des position et posture de la sonde à ultrasons en utilisant la valeur de commande calculée par l'unité de calcul de valeur de commande et d'une unité (2985, 2976) de présentation d'information de guidage qui présente de l'information pour guider le mouvement des position et posture de la sonde à ultrasons en utilisant la valeur de commande calculée par l'unité de calcul de valeur de commande,

caractérisé :

en ce qu'il est prévu une pluralité de boutons ou une liste d'éléments d'examen montrée sur un écran d'image pour choisir un élément d'examen ;

en ce qu'il est prévu une unité (2032) d'obtention de forme pour obtenir, à partir d'une base de données (2031) qui mémorise de l'information de forme sur la forme d'un objet à examiner pour chaque élément d'examen, l'information de forme correspondant à l'élément d'examen choisi par l'unité (2003) de choix ; et

en ce que l'unité de mesure est constituée pour mesurer la position relative et la posture relative en se basant sur le résultat de détection d'une section (2032) de détection de région qui est constituée pour détecter l'objet à examiner en se basant sur l'information de forme obtenue par l'unité (2032) d'obtention de forme dans l'information d'image acquise par la sonde à ultrasons (1001).

2. Système d'imagerie de diagnostic aux ultrasons selon la revendication 1, dans lequel il est prévu une unité (2032) d'obtention de position cible pour obtenir, à partir d'une seconde base de données (2033) qui mémorise des position et posture cibles de la sonde à ultrasons (1001) par rapport à l'objet à examiner pour chaque élément d'examen, les position et posture cibles de la sonde à ultrasons correspondant à l'élément d'examen choisi par l'unité (2003) de choix, dans lequel l'unité (2034) de mesure est constituée pour calculer une correspondance entre les position et posture cibles obtenues et les position et posture de la sonde à ultrasons, et dans lequel l'unité (2035) de calcul de valeur de commande est constituée pour calculer (S110) la valeur de commande des position et posture de la sonde à ultrasons à envoyer au mécanisme (2004) de commande de sonde de façon à rapprocher les position et posture de la sonde à ultrasons de la position cible obtenue lorsque la sonde à ultrasons n'a pas atteint la position cible obtenue.
3. Système d'imagerie de diagnostic aux ultrasons selon la revendication 2, dans lequel la sonde à ultrasons est commandée (S110 à S111) pour atteindre la position cible obtenue, et dans lequel il est prévu un mécanisme (2004) de commande de sonde pour changer (S106) les position et posture de la sonde à ultrasons de façon que l'objet à examiner tombe à l'intérieur d'une plage d'imagerie si l'unité (2032)

de détection de région ne peut pas détecter l'objet à examiner.

4. Système d'imagerie de diagnostic aux ultrasons selon l'une quelconque des revendications 1 à 3, dans lequel la sonde à ultrasons (1001) comprend une unité de mesure de pression qui mesure une pression entre la sonde à ultrasons et le sujet examiné (1005).

5. Système d'imagerie de diagnostic aux ultrasons selon l'une quelconque des revendications 1 à 4, dans lequel la base de données (2031, 2033) enregistre de l'information au sujet de la pression entre la sonde à ultrasons (1001) et le sujet examiné (1005).

6. Procédé de commande pour un système d'imagerie de diagnostic aux ultrasons pourvu d'une sonde à ultrasons (1001) et d'une section (2023) de traitement d'image qui convertit, en information d'image, un signal engendré lorsque la sonde à ultrasons reçoit des ultrasons réfléchis par un sujet examiné (1005), comprenant :

une étape de mesure consistant à mesurer la position relative et la posture relative de la sonde à ultrasons par rapport au sujet examiné en utilisant l'information d'image du sujet examiné acquise par la sonde à ultrasons ;
une étape de calcul de valeur de commande consistant à calculer, en se basant sur le résultat de mesure, une valeur de commande des position et posture de la sonde à ultrasons ; et
au moins l'une d'une étape de commande de sonde consistant à commander des position et posture de la sonde à ultrasons à l'aide d'un mécanisme (2004) de commande de sonde en utilisant la valeur de commande calculée et d'une étape de présentation d'information de guidage consistant à présenter de l'information pour guider le mouvement des position et posture de la sonde à ultrasons en utilisant la valeur de commande calculée par l'unité de calcul de valeur de commande,

caractérisé par :

une étape de choix consistant à choisir un élément d'examen ;
une étape d'obtention de forme consistant à obtenir, à partir d'une base de données (2031) qui mémorise de l'information de forme sur la forme d'un objet à examiner pour chaque élément d'examen, l'information de forme correspondant à l'élément d'examen choisi à l'étape de choix,
dans lequel l'étape de mesure mesure la position relative et la posture relative en se basant sur le résultat de détection d'une étape de détection de région consistant à détecter l'objet à examiner en se basant sur l'information de forme obtenue à l'étape d'obtention de forme dans l'information d'image acquise par la sonde à ultrasons (1001).

7. Procédé de commande selon la revendication 6, comprenant en outre :

une étape d'obtention de position cible consistant à obtenir, à partir d'une seconde base de données (2033) qui mémorise des position et posture cibles de la sonde à ultrasons (1001) par rapport à l'objet à examiner pour chaque élément d'examen, les position et posture cibles de la sonde à ultrasons correspondant à l'élément d'examen choisi à l'étape de choix,
dans lequel l'étape de mesure calcule une correspondance entre les position et posture cibles obtenues et les position et posture de la sonde à ultrasons, et
dans lequel l'étape de calcul de valeur de commande calcule (S110) la valeur de commande des position et posture de la sonde à ultrasons à envoyer au mécanisme (2004) de commande de sonde de façon à rapprocher les position et posture de la sonde à ultrasons de la position cible obtenue lorsque la sonde à ultrasons n'a pas atteint la position cible obtenue.

8. Procédé de commande selon la revendication 7, dans lequel la sonde à ultrasons est commandée (S110 à S111) pour atteindre la position cible obtenue, et
dans lequel le procédé de commande comprend en outre :

une étape de commande de sonde consistant à changer (S106) les position et posture de la sonde à ultrasons de façon que l'objet à examiner tombe à l'intérieur d'une plage d'imagerie si l'étape de détection de région ne peut pas détecter l'objet à examiner.

9. Procédé de commande selon l'une quelconque des revendications 6 à 8, comprenant en outre une étape de mesure de pression consistant pour la sonde à ultrasons à mesurer une pression entre la sonde à ultrasons et le sujet examiné (1005).

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10. Procédé de commande selon l'une quelconque des revendications 6 à 9, comprenant en outre une étape d'enregistrement consistant, pour la base de données, à enregistrer de l'information au sujet de la pression entre la sonde à ultrasons (1001) et le sujet examiné (1005).

5 **11.** Programme destiné à mettre en oeuvre le procédé de commande selon l'une quelconque des revendications 6 à 10.

12. Support d'enregistrement qui enregistre un programme destiné à mettre en oeuvre le procédé de commande selon l'une quelconque des revendications 6 à 10.

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FIG. 1

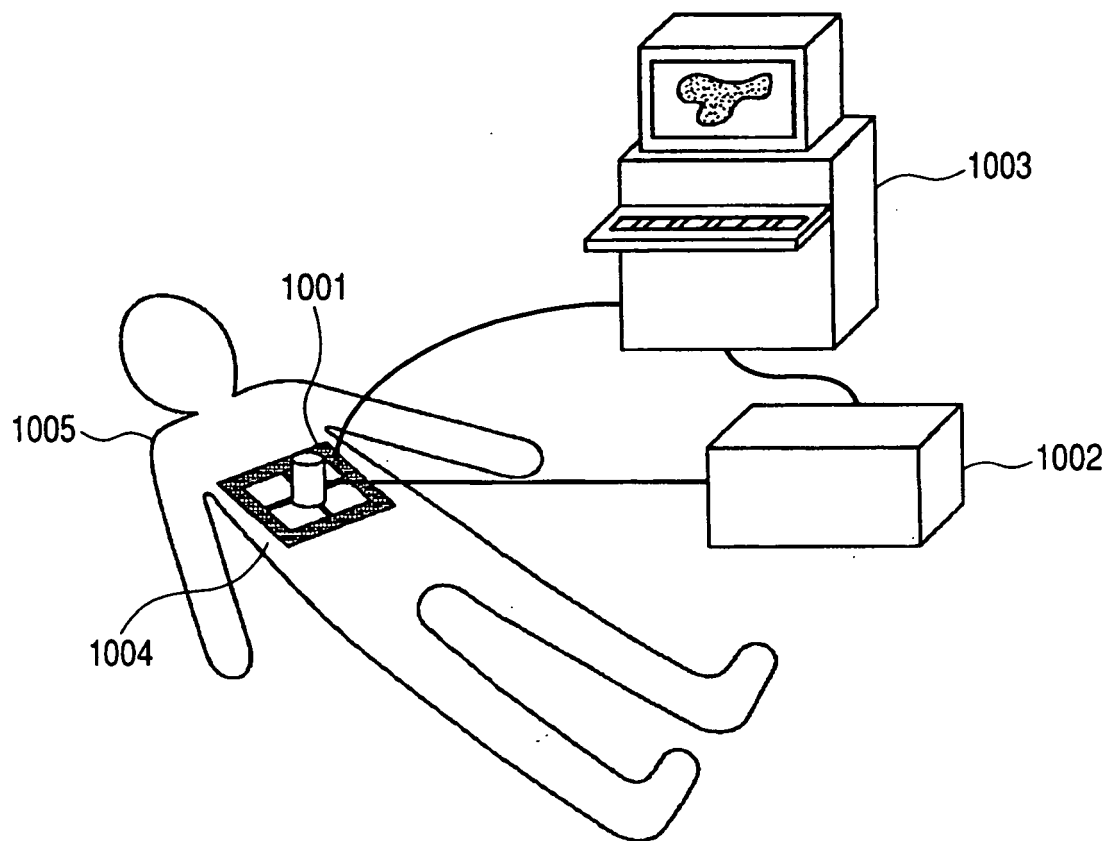


FIG. 2

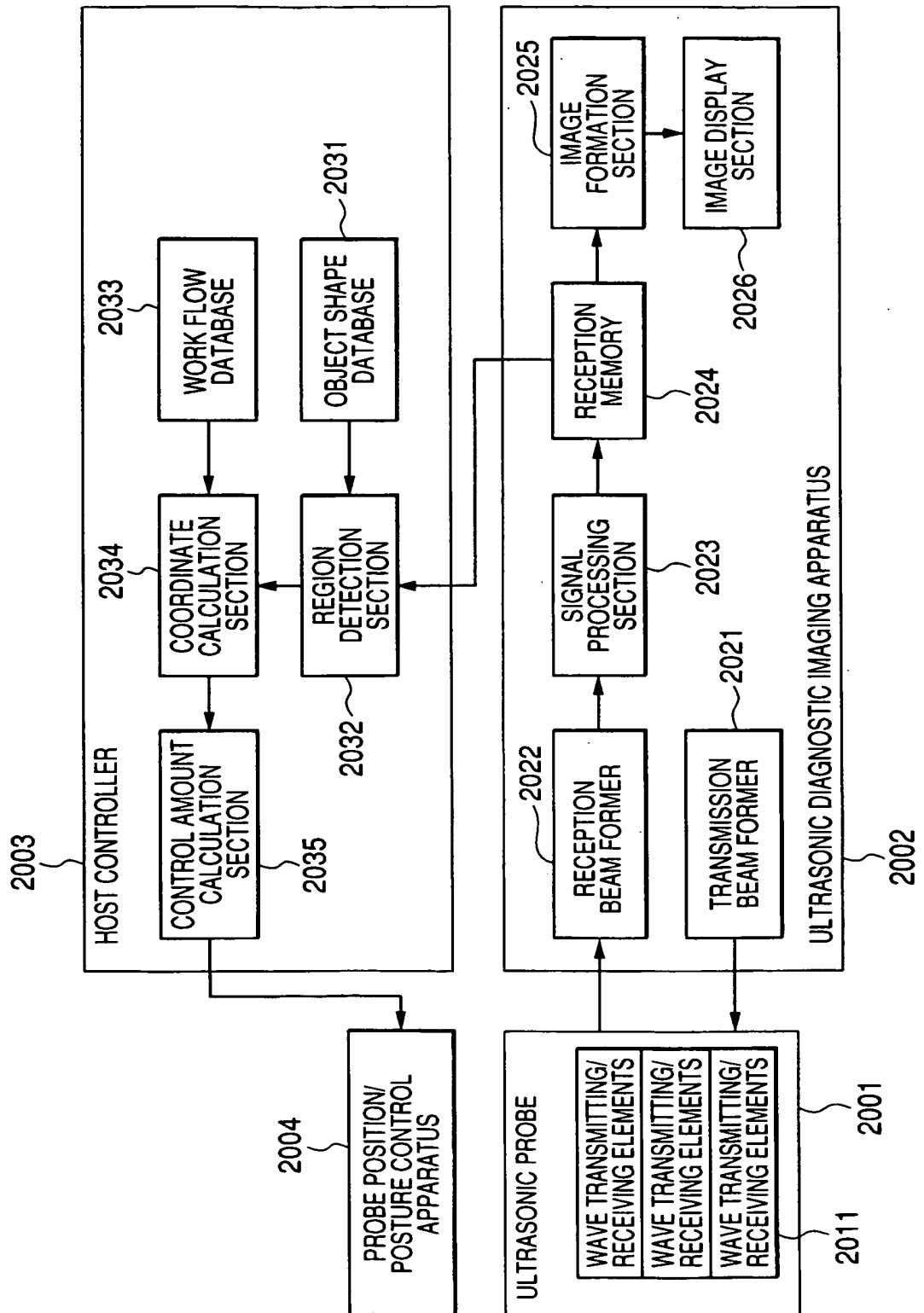


FIG. 3

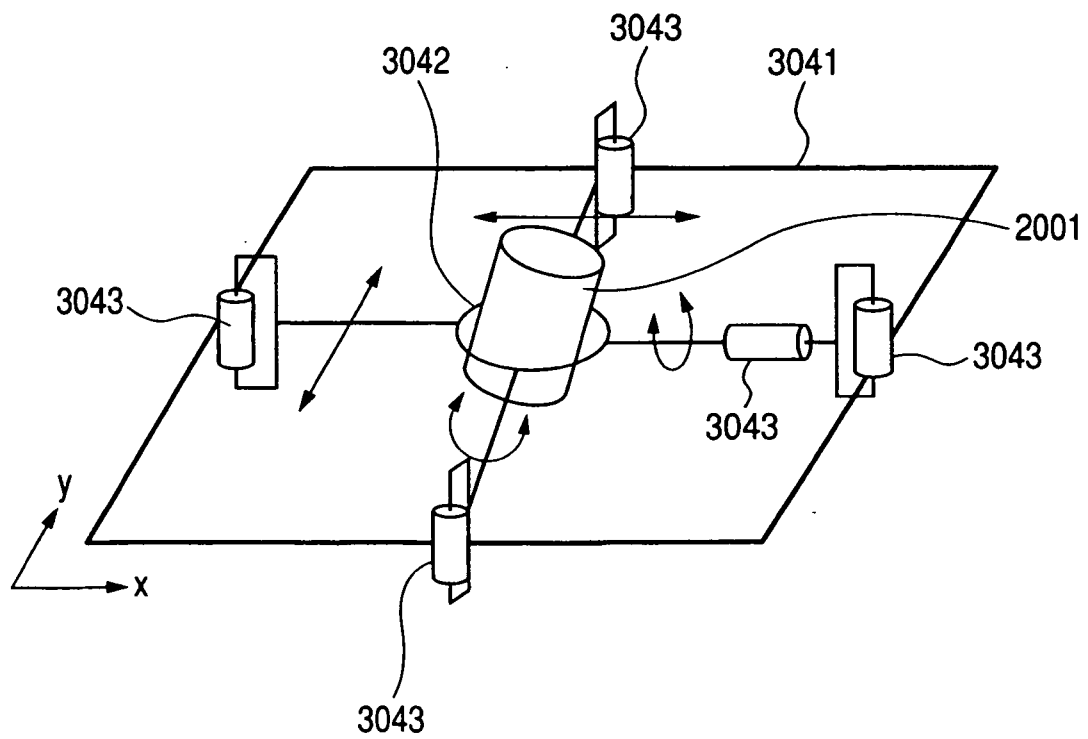


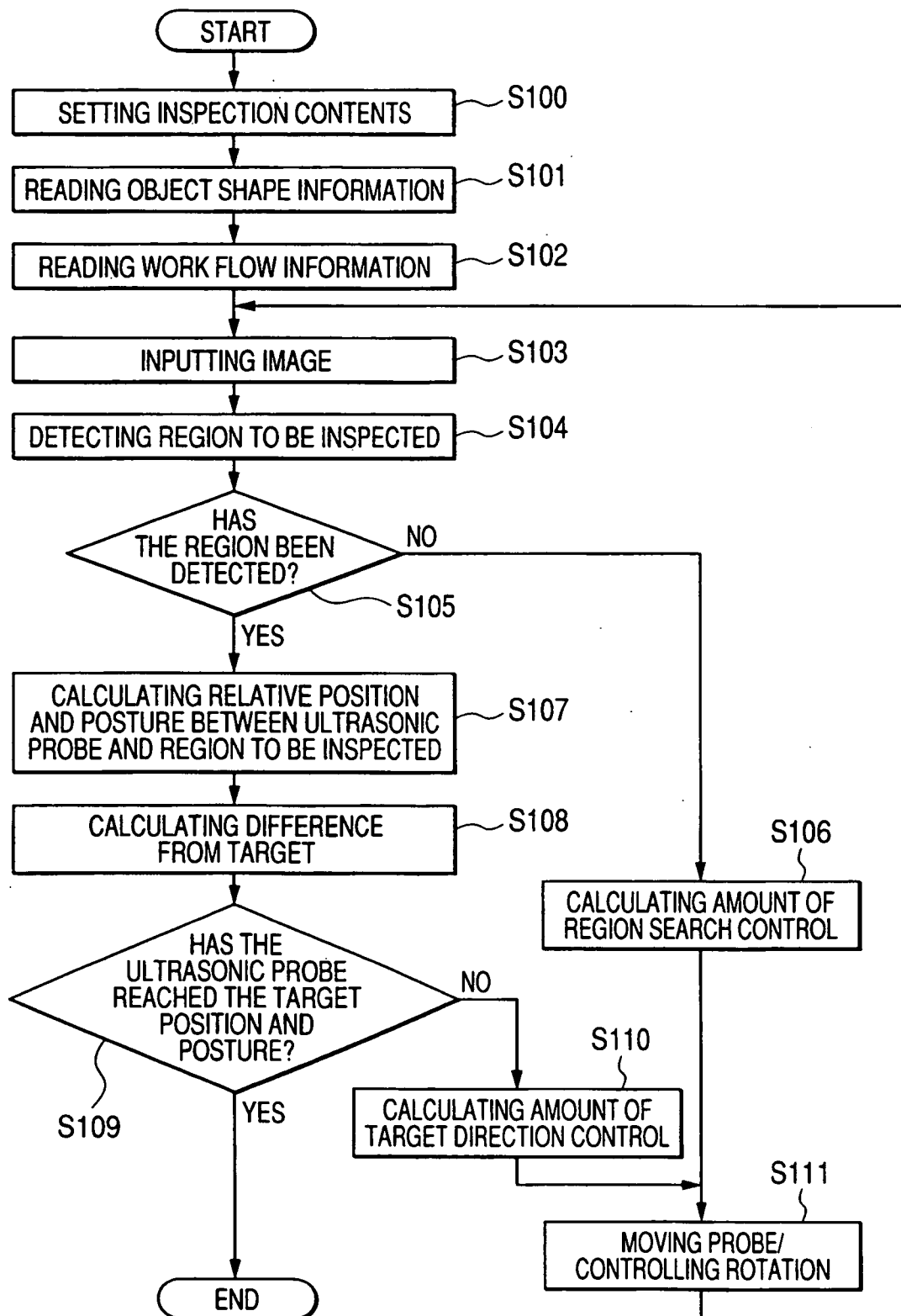
FIG. 4

FIG. 5

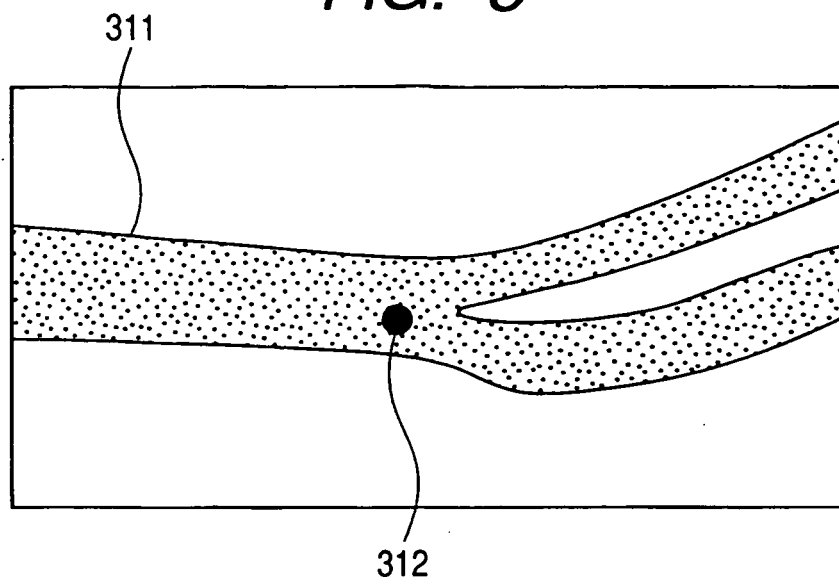


FIG. 6

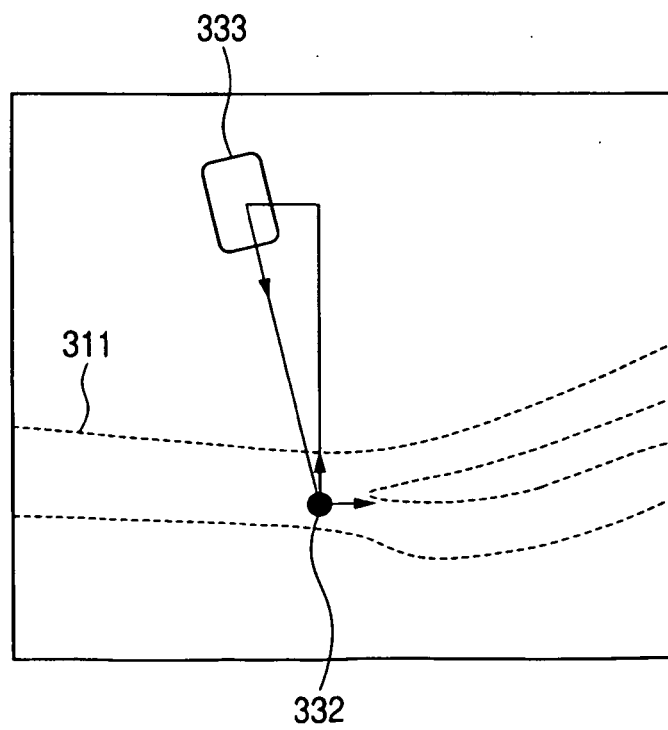


FIG. 7A

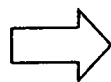
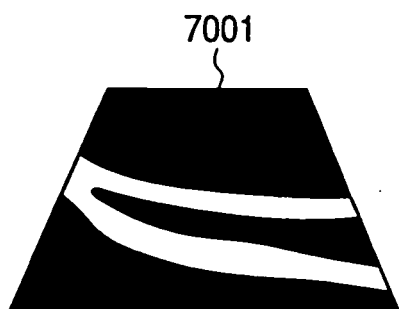


FIG. 7B

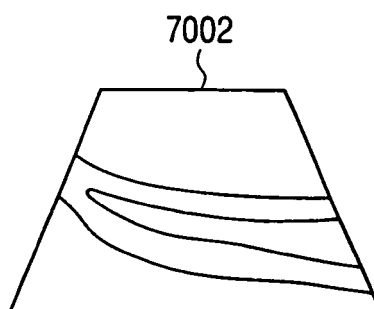


FIG. 7C

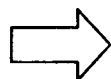
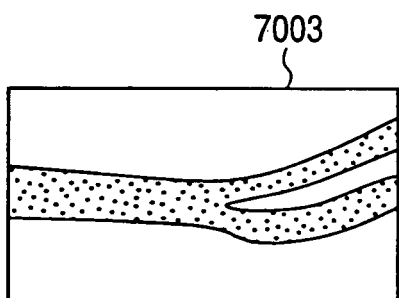


FIG. 7D

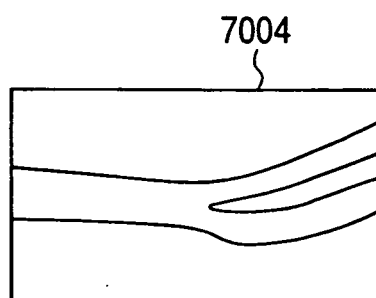


FIG. 7E

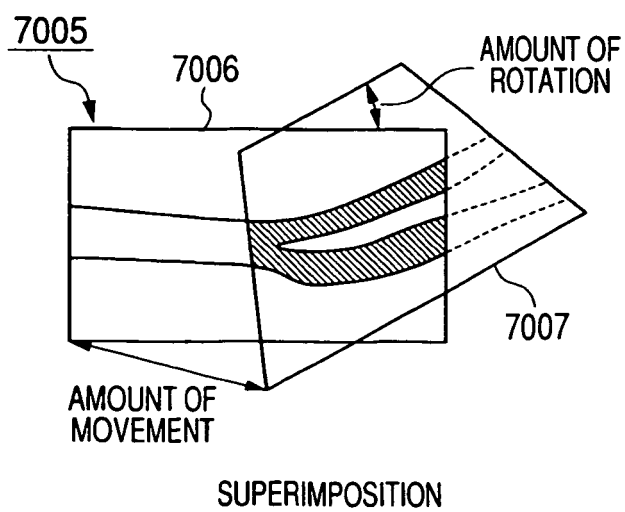


FIG. 8

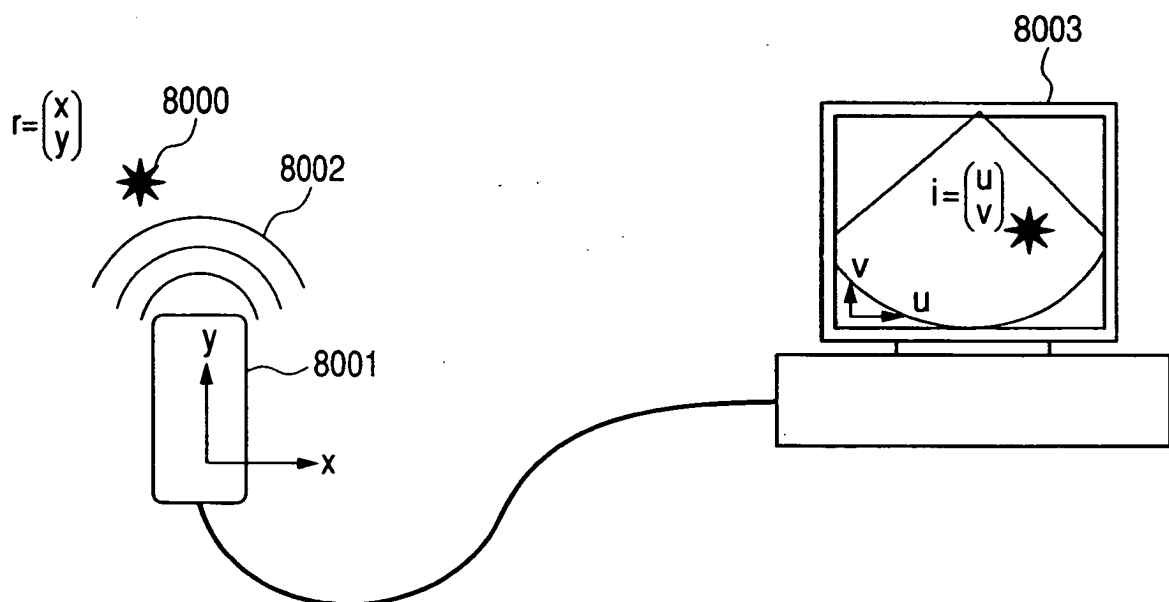


FIG. 9A

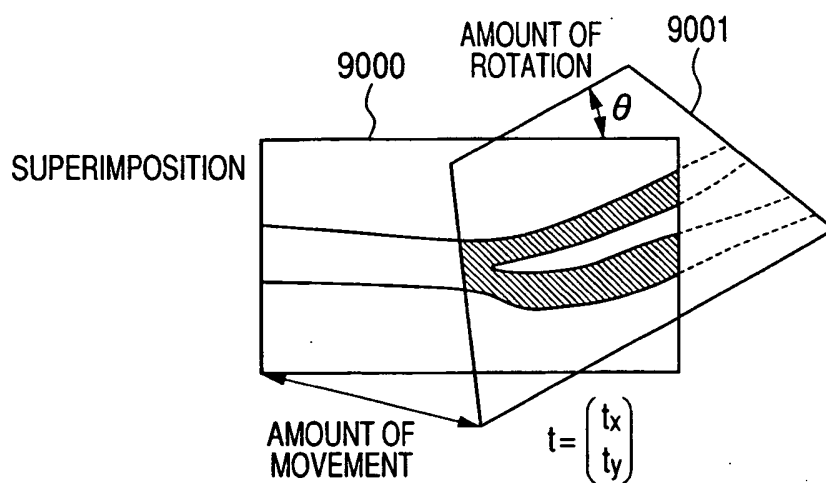


FIG. 9B

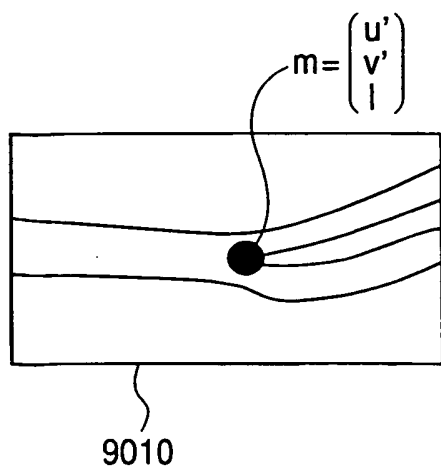


FIG. 9C

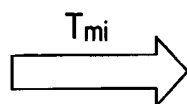
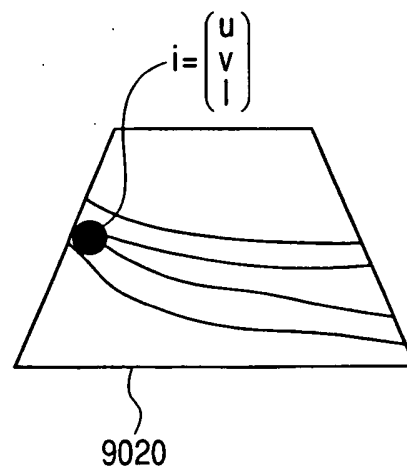


FIG. 10

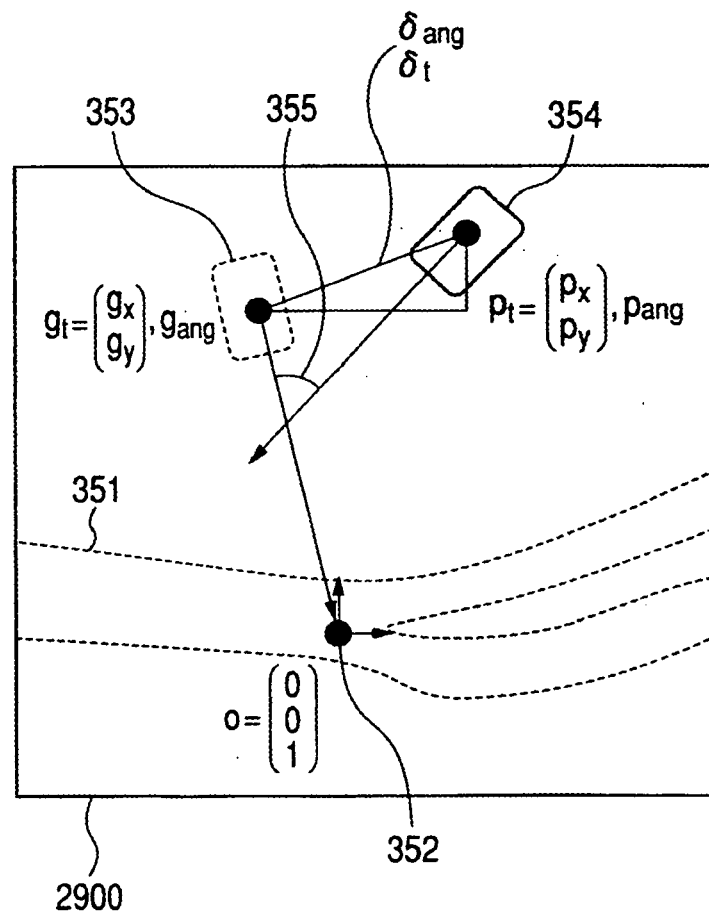


FIG. 11

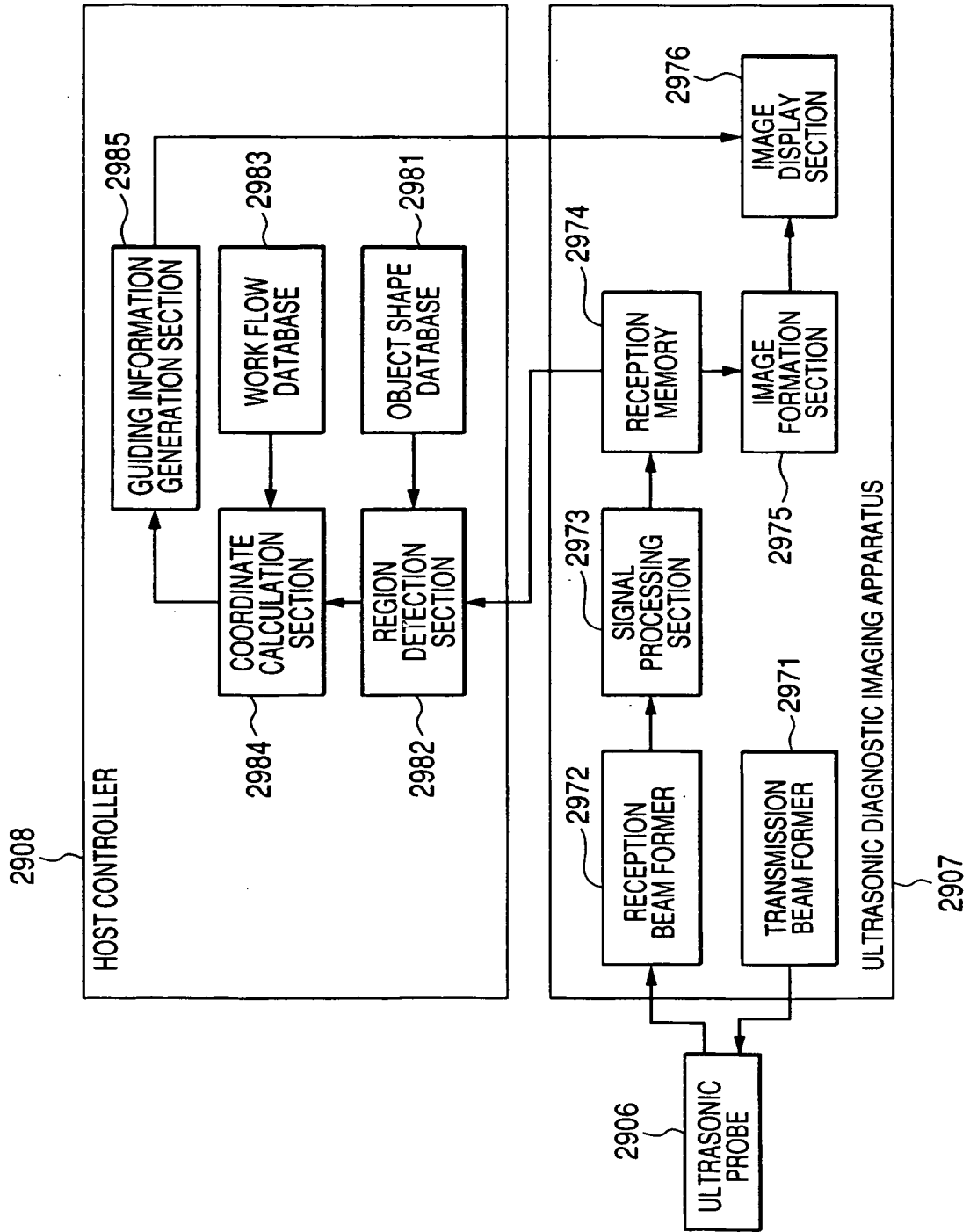


FIG. 12A

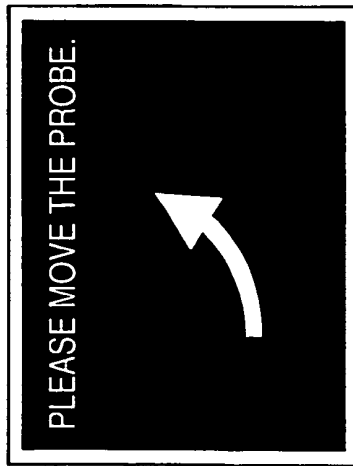


FIG. 12B

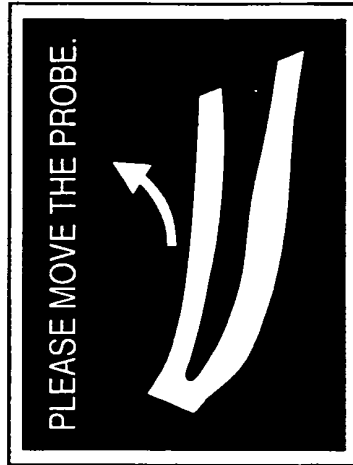
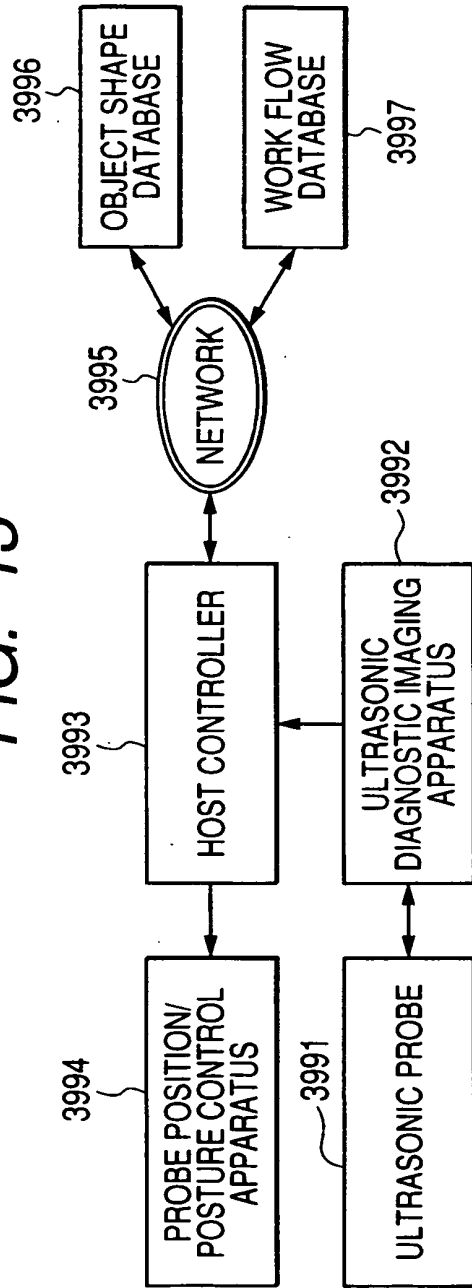


FIG. 13



REFERENCES CITED IN THE DESCRIPTION

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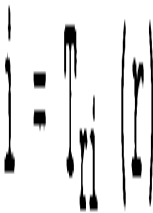
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- JP H01025576 B [0005]
- US 6425865 B1 [0008]
- EP 1348377 A1 [0009]
- US 20040019270 A1 [0010]

专利名称(译)	超声诊断成像系统及其控制方法		
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[标]申请(专利权)人(译)	佳能株式会社		
申请(专利权)人(译)	佳能株式会社		
当前申请(专利权)人(译)	佳能株式会社		
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代理机构(译)	TBK		
优先权	2007226340 2007-08-31 JP		
其他公开文献	EP2185077A1		
外部链接	Espacenet		

摘要(译)

提供了一种不依赖于操作该装置的操作者的超声波诊断成像系统。该系统包括测量单元（坐标计算部分2034），其使用关于由超声波探头获取的被检者的图像信息测量超声波探头相对于被检者的相对位置和相对姿势，控制量计算单元（2035）计算超声波探头的位置和姿势的控制量，基于测量单元的测量结果和探测器控制机构中的至少一个，该探测器控制机构使用由下式计算的控制量来控制超声波探头的位置和姿势。控制量计算单元和引导信息呈现单元，其使用由控制量计算单元计算的控制量来呈现用于引导超声波探头的位置和姿势的移动的信息。



(Expression 1)