

(19)



(11)

EP 3 213 682 B1

(12)

EUROPEAN PATENT SPECIFICATION

(45) Date of publication and mention of the grant of the patent:

04.03.2020 Bulletin 2020/10

(51) Int Cl.:

A61B 5/103 <small>(2006.01)</small>	A61B 8/14 <small>(2006.01)</small>
A61B 8/00 <small>(2006.01)</small>	G06T 17/00 <small>(2006.01)</small>
A61B 34/10 <small>(2016.01)</small>	A61B 90/00 <small>(2016.01)</small>
A61B 34/20 <small>(2016.01)</small>	G06T 7/12 <small>(2017.01)</small>
G06T 7/149 <small>(2017.01)</small>	G06T 7/174 <small>(2017.01)</small>
A61B 8/08 <small>(2006.01)</small>	

(21) Application number: **17163447.0**

(22) Date of filing: **02.08.2011**

(54) METHOD AND APPARATUS FOR THREE DIMENSIONAL RECONSTRUCTION OF A JOINT USING ULTRASOUND

VERFAHREN UND VORRICHTUNG FÜR DREIDIMENSIONALE REKONSTRUKTION EINES GELENKS MIT ULTRASCHALL

PROCÉDÉ ET APPAREIL DE RECONSTRUCTION TRIDIMENSIONNELLE D'UNE ARTICULATION À L'AIDE D'ULTRASONS

(84) Designated Contracting States:
AL AT BE BG CH CY CZ DE DK EE ES FI FR GB GR HR HU IE IS IT LI LT LU LV MC MK MT NL NO PL PT RO RS SE SI SK SM TR

(30) Priority: **02.08.2010 US 369848 P**
01.04.2011 US 201161470952 P

(43) Date of publication of application:
06.09.2017 Bulletin 2017/36

(60) Divisional application:
20153881.6

(62) Document number(s) of the earlier application(s) in accordance with Art. 76 EPC:
11761178.0 / 2 600 766

(73) Proprietor: **Jointvue, LLC**
Colombus, OH 43212-1155 (US)

(72) Inventor: **MAHFOUZ, Mohamed, R.**
Knoxville, TN 37922 (US)

(74) Representative: **HGF Limited**
1 City Walk
Leeds LS11 9DX (GB)

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Description**FIELD OF THE INVENTION**

5 [0001] The present invention relates generally to methods of generating 3-D models of musculoskeletal systems and, more particularly, to ultrasound based 3-D bone and cartilage model reconstruction.

BACKGROUND OF THE INVENTION

10 [0002] The reconstruction of a 3-D model for the knee's articulating bones is a key component of computer-aided knee surgery systems. The existence of a pre-operatively acquired model enables the surgeon to pre-plan a surgery by choosing the proper implant size, calculating the femoral and tibial cutting planes, and evaluating the fit of the chosen implant. The conventional method of generating the 3-D model is segmentation of computed tomography ("CT"), or magnetic resonance imaging ("MRI") scans, which are the conventional imaging modalities for creating patient-specific 3-D bone models. The segmentation methods used are either manually, semi-automatic, or fully automated. Although these methods produce highly accurate models, CT and MRI have inherent draw backs, i.e., both are fairly expensive procedures (especially for the MRI), and CT exposes the patient to ionizing radiation. These limitations have motivated the research of new methods for acquiring and reconstructing bone models.

15 [0003] One alternative method of forming patient-specific models is the use of previously acquired X-Ray images as *a priori* information to guide the morphing of a template bone model whose projection matches the X-Ray images. Several X-Ray based model reconstruction methodologies have been developed for the femur (including, specifically, the proximal and distal portions), the pelvis, the spine, and the rib cage.

20 [0004] Conventional ultrasound imaging utilizes the B-mode images. B-mode images are constructed by extracting an envelope of received scanned lines of radiofrequency ("RF") signals using the Hilbert transformation. These envelopes are then decimated (causing a drop in the resolution) and converted to grayscale (usually 256 bit) to form the final B-mode image. The conversion to grayscale results in a drop in the dynamic range of the ultrasound data.

25 [0005] The use of ultrasound in computer aided orthopedic surgery has gained a lot of interest in the recent decade due to its relatively low cost and radiation-free nature. More particularly, A-mode ultrasound intra-operative registration has been used for computer aided orthopedic surgery and, in limited cases, in neurosurgery. Ultrasound-MRI registration has been developed utilizing B-mode ultrasound images. Document US6106464 A describes an A-mode ultrasound transducer that is tracked in three-dimensions by an optical position tracking system as the transducer is scanned over the skin to generate measurements of bone surface distance from the transducer.

30 [0006] Therefore, it would be desirable to develop a method of utilizing ultrasound techniques to construct 3-D patient-specific bone and cartilage models.

SUMMARY OF THE INVENTION

35 [0007] The present invention overcomes the foregoing problems and other shortcomings, drawbacks, and challenges of high cost or high radiation exposure imaging modalities to generate a patient-specific model by ultrasound techniques. While the present invention will be described in connection with certain embodiments, it will be understood that the present invention is not limited to these embodiments. To the contrary, this invention includes all alternatives, modifications, and equivalents as may be included within the scope of the appended claims. In accordance with aspects of the of the invention, there is provided a method of generating a 3-D patient-specific musculoskeletal model, and an ultrasound instrument for generating a 3-D patient-specific musculoskeletal model, in accordance with the appended claims.

40 [0008] In accordance with one embodiment of the present invention, a method of generating a 3-D patient-specific bone model is described. The method includes acquiring a plurality of raw radiofrequency ("RF") signals from an A-mode ultrasound scan of the bone, which is spatially tracked in 3D space. The bone contours are isolated in each of the plurality of RF signals and transformed into a point cloud. A 3-D bone model of the bone is then optimized with respect to the point cloud.

45 [0009] According to another embodiment of the present invention, a method for 3-D reconstruction of a bone surface includes imaging the bone with A-mode ultrasound. A plurality of RF signals is acquired while imaging. Imaging of the bone is also tracked. A bone contour is extracted from each of the plurality of RF signals. Then, using the tracked data and the extracted bone contours, a point cloud representing the surface of the bone is generated. A model of the bone is morphed to match the surface of the bone as represented by the point cloud.

50 [0010] In still yet another embodiment of the present invention, a computer method for simulating a surface of a bone is described. The computer method includes executing a computer program in accordance with a process. The process includes extracting a bone contour from each of a plurality of A-mode RF signals. The extracted bone contours are transformed from a local frame of reference into a point cloud in a world-frame of reference. A generalized model of the

bone is compared with the point cloud and, as determined from the comparing, the generalized model is deformed to match the point cloud.

[0011] Another embodiment of the present invention is directed to a computer program product that includes a non-transitory computer readable medium and program instructions stored on the computer readable medium. The program instructions, when executed by a process, cause the computer program product to isolate a bone contour from a plurality of RF signals. The plurality of RF signals being previously acquired from a reflected A-mode ultrasound beam. The bone contours are then transformed into a point cloud and used to optimize a 3-D bone model of the bone.

[0012] Still another embodiment of the present invention is directed to a computing device having a processor and a memory. The memory includes instructions that, when executed by the processor, cause the processor to isolate a bone contour from a plurality of RF signals. The plurality of RF signals being previously acquired from a reflected A-mode ultrasound beam. The bone contours are then transformed into a point cloud and used to optimize a 3-D bone model of the bone.

BRIEF DESCRIPTION OF THE FIGURES

[0013] The accompanying drawings, which are incorporated in and constitute a part of this specification, illustrate embodiments of the present invention and, together with the detailed description of the embodiments given below, serve to explain the principles of the present invention.

FIG. 1 is a perspective view of an ultrasound instrument in accordance with one embodiment of the present invention. FIG. 2 is a perspective view of a hybrid probe comprising an ultrasound probe and an optical marker, in accordance with one embodiment of the present invention.

FIG. 2A is a side elevational view of a position sensor for use with the optical marker of the hybrid probe.

FIG. 3 is a diagrammatic view of a computer system suitable for generating a 3-D patient-specific bone model from A-mode ultrasound RF signals in accordance with one embodiment of the present invention.

FIG. 4 is a flow chart illustrating one exemplary method of calibrating the optical system and generating a transformation between a local frame and a world frame.

FIGS. 5A-5C are diagrammatic views of a knee joint, showing the anterior, the medial, and the posterior portions, respectively.

FIGS. 6A-6F are fluoroscopic images of the knee joint in a plurality of degrees of flexion.

FIG. 7 is a flow chart illustrating one exemplary method of acquiring A-mode ultrasound RF signal and generating the 3-D patient-specific bone model.

FIG. 8 is a diagrammatic view of the method of acquiring A-mode ultrasound RF signals in accordance with FIG. 7.

FIG. 9 is a B-mode ultrasound image of a knee joint, which may optionally be shown from the A-mode ultrasound RF signal.

FIG. 10A is an example of a raw RF signal as acquired by one transducer of the transducer array of an ultrasound probe.

FIG. 10B is the ultrasound frame illustrates select ones of the RF signals overlaid the B-mode ultrasound image of FIG. 9.

FIG. 10C is the ultrasound frame of FIG. 10B with a bone echo contour identified.

FIG. 10D is a 3-D rendering of the RF signals acquired in a data frame, which is shown in the B-mode image format in FIG. 10C.

FIG. 10E is another 3-D rendering of an ultrasound frame with select ones of the RF signals delineated.

FIG. 11 is a flow chart illustrating one exemplary method of identifying and extracting the bone echo from the A-mode ultrasound RF signal.

FIG. 12A is a 3-D rendering of an ultrasound frame after envelope detection.

FIGS. 12B-12E respectively illustrate four exemplary envelopes of the sampled A-mode ultrasound RF signal, with the echoes identified in each envelope.

FIGS. 13A and 13D are B-mode ultrasound frames calculated from exemplary A-mode ultrasound RF signals.

FIGS. 13B and 13E are ultrasound frames corresponding to FIGS. 13A and 13D, respectively, with a bone contour identified before noise removal and overlain on the B-mode image.

FIGS. 13C and 13F are plots of the local standard deviation of the bone contours of FIGS. 13B and 13E, respectively.

FIGS. 14A and 14D are ultrasound frames illustrating exemplary B-mode images constructed from A-mode ultrasound RF signals, and in which no bone tissue was scanned.

FIGS. 14B and 14E are ultrasound frames corresponding to FIGS. 14A and 14D, respectively, with the noisy false bone contours shown.

FIGS. 14C and 14F are plots of the local standard deviation of the last echoes of FIGS. 14B and 14E, respectively.

FIG. 15 is a flow chart illustrating one exemplary method of generating a bone point cloud from the isolated bone

contours.

FIGS. 16A, 16C, 17A, and 17C are exemplary bone point clouds, generated in accordance with one embodiment of the present invention.

FIGS. 16B, 16D, 17B, and 17D are examples in which the bone point clouds of FIGS. 16A, 16C, 17A, and 17C, respectively, are aligned to a bone model.

FIG. 18 is a flow chart illustrating one exemplary method of generating a statistical atlas of bone models.

FIG. 19 is a flow chart illustrating one exemplary method of optimizing a bone model to the bone point cloud.

DETAILED DESCRIPTION OF THE EMBODIMENTS OF THE INVENTION

[0014] The various embodiments of the present invention are directed to methods of generating a 3-D patient-specific bone model. To generate the 3-D patient-specific model, a plurality of raw RF signals is acquired using A-mode ultrasound acquisition methodologies. A bone contour is then isolated in each of the plurality of RF signals and transformed into a point cloud. The point clouds may then be used to optimize a 3-D bone model of the bone such that the patient-specific model may be generated.

[0015] Turning now to the figures, and in particular to FIG. 1, one embodiment of an ultrasound instrument 50 for use with one or more embodiments of the present invention is shown. The ultrasound instrument 50 should be configurable such that the user may access acquired RF ultrasound data. One suitable instrument may, for example, include the diagnostic ultrasound model SonixRP by Ultrasonix Inc. (Richmond, British Columbia, Canada). The ultrasound instrument 50 includes a housing 52 containing a controller, (for example, a computer 54), an energy or power source (not shown), a user input device 56, an output device (for example, a monitor 58), and at least one ultrasound probe 60. The housing 52 may include caster wheels 62 for transporting the ultrasound instrument 50 within the medical facility.

[0016] The at least one ultrasound probe 60 is configured to acquire ultrasound raw radiofrequency ("RF") signals, and is shown in greater detail in FIG. 2. The ultrasound probe 60, such as the particular embodiment shown, may be a high resolution linear transducer with a center frequency of 7.5 MHz, as is conventionally used in musculoskeletal procedures. The sampling frequency used in digitizing ultrasound echo may be, for example, 20 MHz and must be at least twice the maximum ultrasound frequency. Generally, the ultrasound probe 60 includes a body 64 that is coupled to the ultrasound instrument housing 52 (FIG. 1) by a cable 66. The body 64 further includes a transducer array 68 configured to transmit an ultrasound pulse and to receive reflected ultrasound RF energy. The received RF echo is transmitted along the cable 66, to the computer 54 of the ultrasound instrument 50 (FIG. 1) for processing in accordance with an embodiment of the present invention.

[0017] The computer 54 of the ultrasound instrument 50 (FIG. 1), as shown in FIG. 3, may be considered to represent any type of computer, computer system, computing system, server, disk array, or programmable device such as multi-user computers, single-user computers, handheld devices, networked devices, or embedded devices, etc. The computer 54 may be implemented with one or more networked computers 70 or networked storage devices 72 using one or more networks 74, e.g., in a cluster or other distributed computing system through a network interface 76 (illustrated as "NETWORK I/F"). For brevity's sake, the computer 54 will be referred to simply as "computer," although it should be appreciated that the term "computing system" may also include other suitable programmable electronic devices consistent with embodiments of the present invention.

[0018] The computer 54 typically includes at least one processing unit 78 (illustrated as "CPU") coupled to a memory 80 along with several different types of peripheral devices, e.g., a mass storage device 82, the user interface 84 (illustrated as "User I/F," which may include the input device 56 (FIG. 1) and the monitor 58 (FIG. 1)), and the Network I/F 76. The memory 80 may include dynamic random access memory ("DRAM"), static random access memory ("SRAM"), non-volatile random access memory ("NVRAM"), persistent memory, flash memory, at least one hard disk drive, and/or another digital storage medium. The mass storage device 82 is typically at least one hard disk drive and may be located externally to the computer 54, such as in a separate enclosure or in one or more of the networked computers 70, one or more of the networked storage devices 72 (for example, a server)

[0019] The CPU 78 may be, in various embodiments, a single-thread, multi-threaded, multi-core, and/or multi-element processing unit (not shown) as is well known in the art. In alternative embodiments, the computer 54 may include a plurality of processing units that may include single-thread processing units, multi-threaded processing units, multi-core processing units, multi-element processing units, and/or combinations thereof as is well known in the art. Similarly, the memory 80 may include one or more levels of data, instruction, and/or combination caches, with caches serving the individual processing unit or multiple processing units (not shown) as is well known in the art.

[0020] The memory 80 of the computer 54 may include an operating system 81 (illustrated as "OS") to control the primary operation of the computer 54 in a manner that is well known in the art. The memory 80 may also include at least one application, component, algorithm, program, object, module, or sequence of instructions, or even a subset thereof, will be referred to herein as "computer program code" or simply "program code," (illustrated as same, 83). Program code 83 typically comprises one or more instructions that are resident at various times in the memory 80 and/or the mass

storage device 82 of the computer 54, and that, when read and executed by the CPU 78, causes the computer 54 to perform the steps necessary to execute steps or elements embodying the various aspects of the present invention.

[0021] Those skilled in the art will recognize that the environment illustrated in FIG. 3 is not intended to limit the present invention. Indeed, those skilled in the art will recognize that other alternative hardware and/or software environments may be used without departing from the scope of the present invention.

[0022] Returning again to FIG. 2, the ultrasound probe 60 has mounted thereto a tracking marker 86, which, for purposes of illustration only, is shown as an optical marker, configured to spatially register the motion of the ultrasound probe 60 during signal acquisition. The tracking marker 86 may be comprised of a plurality of reflective portions 90, which are described in greater detail below. The tracked probe constitutes a hybrid probe 94. In other embodiments, the tracking marker and associated system may be electromagnetic, RF, or any other known 3-D tracking system.

[0023] The optical marker 86 is operably coupled to a position sensor 88, one embodiment of which is shown in FIG. 2A. In use, the position sensor 88 emits energy (for example, infrared light) in a direction toward the optical marker 86. Reflective portions 90 of the optical marker 86 reflect the energy back to the position sensor 88, which then triangulates the 3-D position and orientation of the optical marker 86. One example of a suitable optical tracking system is the Polaris model manufactured by Northern Digital Inc. (Waterloo, Ontario, Canada).

[0024] The optical marker 86 is rigidly attached to the ultrasound probe 60 and is provided a local coordinate frame of reference ("local frame" 92). Additionally, the ultrasound probe 60 is provided another local coordinate frame of reference ("ultrasound frame"). For the sake of convenience, the combination optical marker 86 with the ultrasound probe 60 is referred to as the "hybrid probe" 94. The position sensor 88, positioned away from the hybrid probe 94, determines a fixed world coordinate frame ("world frame").

[0025] Operation of the optical tracking system (the optical marker 86 with the position sensor 88) with the ultrasound probe 60, once calibrated, is configured to determine a transformation between the local and ultrasound coordinate frames.

[0026] Turning now to FIG. 4, with reference also to FIG. 2, a method 100 of calibrating the optical tracking system according to one embodiment of the present invention is described. To calibrate the optical marker 86 with the position

sensor 88, for real-time tracking of the hybrid probe 94, a homogeneous transformation T_{OP}^W between the local frame, OP, and the world frame, W, is needed. The calibration method 100 begins with determining a plurality of calibration parameters (Block 102). In the particular illustrative example, four parameters are used and include: P_{trans_origin} , i.e., a point of origin on the transducers array 68; L_{trans} , i.e., a length of the transducer array 68; \hat{u}_x , i.e., a unit vector along the length of the transducer array 68; \hat{u}_y , i.e., a unit vector in a direction that is perpendicular to the length of the transducer array 68. These calibration points and vectors are relative to the local frame 92 ("OP").

[0027] The hybrid probe is held in a fixed position while the position sensor 88 optical camera acquires a number of position points, including, for example: P_{trans1} , i.e., a first end of the transducer array 68; P_{trans2} , i.e., a second end of the transducer array 68; and P_{plane} , i.e., a point on the transducer array 68 that is not collinear with P_{trans1} and P_{trans2}

(Block 104). The homogeneous transformation between OP and W, T_{OP}^W , is the recorded (Block 106). The plurality of calibration parameters are then calculated (Block 108) from the measured number of points and the transformation,

T_{OP}^W , as follows:

$$T_W^{OP} = (T_{OP}^W)^{-1} \quad (1)$$

$$P_{trans_origin} = T_W^{OP} P_{trans1} \quad (2)$$

$$L_{trans} = \|P_{trans2} - P_{trans1}\| \quad (3)$$

$$\hat{u}_x = T_W^{OP} \frac{P_{trans2} - P_{trans1}}{\|P_{trans2} - P_{trans1}\|} \quad (4)$$

$$\hat{u}_y = \frac{(P_{plane} - P_{trans1}) \times (P_{trans2} - P_{trans1})}{\|(P_{plane} - P_{trans1}) \times (P_{trans2} - P_{trans1})\|} \quad (5)$$

[0028] With the plurality of calibration parameters determined, the hybrid probe 94 may be used to scan a portion of a patient's musculoskeletal system while the position sensor 88 tracks the physical movement of the hybrid probe 94.

[0029] Because of the high reflectivity and attenuation of bone to ultrasound, ultrasound energy does not penetrate bone tissues. Therefore, soft tissues lying behind bone cannot be imaged and poses a challenge to ultrasound imaging of a joint. For example, as shown in FIGS. 5A-5C, the knee joint 114 is formed of three articulating bones: the femur 116, the tibia 118, and the patella 120, with the fibula 122 shown as environment. These bones 116, 118, 120 articulate together in two sub-joints: (1) the tibio-femoral joint 136 is formed by the articulation of the femur 116 with the tibia 118 at the respective condyles 124, 126, 128, 130 and (2) the patello-femoral joint 138 is formed by the articulation of the patella 120 with the femur 116 at the patellar surface 132 of the femur 116 and the articular surface 134 of the patella 120. During flexion-extension motions of the knee joint 114, portions of one or more articulating surfaces of the bones 116, 118, 120 are visible to the ultrasound beam, while other articulating surfaces are occluded. FIGS. 6A-6F include various fluoroscopic images of one patient's knee joint 114, showing the articulating surfaces at a plurality of degrees of flexion.

[0030] To acquire ultrasound images of a majority of the articulating surfaces, at least two degrees of flexion are required, including, for example, a full extension (FIG. 6A) and a deep knee bend (FIG. 6F) (or 90° flexion (FIG. 6E) if a deep knee bend is too difficult for the patient to achieve). That is, when the knee joint 114 is in the full extension (FIG. 6A), the posterior portions of the distal femur 116 and the proximal tibia 118 are accessible to the ultrasound beam. When the knee joint 114 is in the deep knee bend (FIG. 6F), the anterior surface of the distal femur 116, the trochlear groove 140, most of the inferior surface of the femoral condyles 124, 126, the anterior superior surface of the tibia 118, and the anterior surface of the tibia 118 are accessible to the ultrasound beam. Both the medial and lateral parts of the femur 116 and tibia 118 are visible at all flexion angles of the knee joint 114.

[0031] Turning now to FIG. 7, one method 150 of acquiring data for construction of a 3-D patient-specific bone model is described. The method begins with acquiring a plurality of RF signals from an A-mode ultrasound beam scan of a bone. To acquire the RF signals for creating the 3-D patient-specific model of the knee joint 114, the patient's knee joint 114 is positioned and held in one of the two or more degrees of flexion (Block 152). The hybrid probe 94 is positioned, at two or more locations, on the patient's epidermis 144 adjacent to the knee joint 114 for acquisition of the A-mode RF signal 142, one example, as shown in FIG. 8. Although the acquired signal includes a plurality of RF signals, for convenience, the RF signals are sometimes referred to herein in singular form.

[0032] As shown in FIG. 8, with reference also to FIG. 7, the position of the patient's knee joint 114 is held stationary to avoid motion artifacts during image acquisition. Should motion occur, scans may be automatically aligned to the statistically-most likely position given the data acquired. Furthermore, holding the knee stationary and compensating for movement removes the need for invasive fiducial bone markers or high-error skin markers. In some embodiments, B-mode images, similar to the one shown in FIG. 9, may also be processed from the gathered data (Block 154) for subsequent visualization and overlain with the bone contours, as described in detail below.

[0033] When the RF signal 142, and if desired B-mode image, acquisition is complete for the first degree of flexion, the patient's knee 114 is moved to another degree of flexion and the reflected RF signal 142 acquired (Block 156). Again, if desired, the B-mode image may also be acquired (Block 158). The user then determines whether acquisition is complete or whether additional data is required (Block 160). That is, if visualization of a desired surface of one or more bones 116, 118, 120 is occluded ("NO" branch of decision block 160), then the method returns to acquire additional data at another degree of flexion (Block 156). If the desired bone surfaces are sufficiently visible ("YES" branch of decision block 160), then the method 150 continues.

[0034] FIG. 8 illustrates acquisition of the RF signal 142 in yet another manner. That is, while the patient's leg is in full extension (shown in phantom), the hybrid probe 94 is positioned at two or more locations on the patient's epidermis 144 adjacent to the knee joint 114. The patient's leg is then moved to a second degree of flexion (90° flexion is shown in solid) and the hybrid probe 94 again positioned at two or more locations on the patient's epidermis 144. All the while, the position sensor 88 tracks the location of the hybrid probe 94 in the 3-D space. Resultant RF signal profiles, bone models, bone contours, and so forth may be displayed on the monitor 58 during and the monitor 58' after the model reconstruction.

[0035] After all data and RF signal acquisition is complete, the computer 54 (FIG. 3) is operated to automatically isolate that portion of the RF signal, i.e., the bone contour, from each of the plurality of RF signals. In that regard, the computer 54 (FIG. 3) may sample the echoes comprising the RF signals to extract a bone contour for generating a 3-D point cloud 165 (FIG. 16B) (Block 164). More specifically, and with reference now to FIGS. 10A-10E and 11, with continued reference to FIGS. 7-9, one method 164 of extracting the bone contours from each of the RF signal 142 is shown. FIG. 10A illustrates one exemplary, raw RF signal 142 as acquired by one transducer comprising the transducer array 68 (FIG. 2) of the ultrasound probe portion of the hybrid probe 94 (FIG. 2). Each acquired raw, RF signal includes a number of echoes 162, wherein the echoes 162 may be isolated, partially overlapping, or fully overlapping. Each of the plurality of echoes originates from a reflection of at least a portion of the ultrasound energy at an interface between two tissues having different reflection and/or attenuation coefficients, as described in greater detail below.

[0036] FIGS. 10B and 10C illustrate an ultrasound frame 146 having select ones of the raw RF signals 142 with some echoes 162 identified. FIGS. 10D and 10E are 3-D renderings of 2D images taken from an ultrasound frame 146 with select ones of the RF signals 142 identified in FIG. 10E.

[0037] Referring specifically now to FIG. 11, the method of extracting the bone contour 162a begins with a model-based signal processing approach incorporating *a priori* knowledge of an underlying physical problem into a signal processing scheme. In this way, the computer 54 (FIG. 3) may process the RF signal 142 and remove some preliminary noise based on an estimated, or anticipated, result. For example, with ultrasound signal acquisition, the physical problem is represented by the governing waveform equation, such as described in VARSLOT T, et al., "Computer Simulation of Forward Wave Propagation in Soft Tissue," IEEE Transactions on Ultrasonics, Ferroelectrics, and Frequency Control, 1473-1482:52(9), Sept. 2005. The wave equation describes the propagation behavior of the ultrasonic wave in a heterogeneous medium. The solution to the wave equation may be represented as a state-space model-based processing scheme, such as described in CHEN Z, et al., "Bayesian Filtering: From Kalman Filters to Particle Filters, and Beyond," Statistics, 1 -69, retrieved from <http://citeseerx.ist.psu.edu/viewdoc/download?doi=10.1.1.107.7415&rep=rep1&type=pdf>, accessed Aug. 2011. In accordance with one embodiment of the present invention, a general solution to the model-based ultrasound wave estimator problem is developed using Bayesian estimators (e.g., maximum *a posteriori*), which leads to a nonlinear model-based design.

[0038] The model-based signal processing of the RF signal 142 begins with enhancing the RF signal by applying the model-based signal processing (here, the Bayesian estimator) (Block 167). To apply the Bayesian estimator, offline measurements are first collected from phantoms, cadavers, and/or simulated tissues to estimate certain unknown parameters, for example, an attenuation coefficient (i.e., absorption and scattering) and an acoustic impedance (i.e., density, porosity, compressibility), in a manner generally described in VARSLOT T (refer above), the disclosure of which is incorporated herein by reference, in its entirety. The offline measurements (Block 169) are input into the Bayesian estimator and the unknown parameters are estimated as follows:

$$z = h(x) + v \quad (6)$$

$$P(t) = e^{(-\beta t^2)} \cdot \cos(2\pi \cdot f_0 \cdot t) \quad (7)$$

Where h is the measurement function that models the system and v is the noise and modeling error. In modeling the system, the parameter, x , that best fits the measurement, z , is determined. For example, the data fitting process may find an estimate of \hat{x} that best fits the measurement of z by minimizing some error norm, $\|\epsilon\|$, of the residual, where:

$$\epsilon = z - h(\hat{x}) \quad (8)$$

[0039] For ultrasound modeling, the input signal, z , is the raw RF signal from the offline measurements, the estimate $h(\hat{x})$ is based on the state space model with known parameters of the offline measurements (i.e., density, etc.). The error, v , may encompass noise, unknown parameters, and modeling errors in an effort to reduce the effect of v minimizing the residuals and identifying the unknown parameters from repeated measurements. Weighting the last echo within a scan line by approximately 99%, as bone, is one example of using likelihood in a Bayesian framework. A Kalman filter may alternatively be used, which is a special case of the recursive Bayesian estimation, in which the signal is assumed to be linear and have a Gaussian distribution.

[0040] It would be readily appreciated that the illustrative use of the Bayesian model here is not limiting. Rather, other model-based processing algorithms or probabilistic signal processing methods may be used within the scope of the appended claims.

[0041] With the model-based signal processing complete, the RF signal 142 is then transformed into a plurality of envelopes to extract the individual echoes 162 existing in the RF signal 142. Each envelope is determined by applying a moving power filter to each RF signal 142 (Block 168) or other suitable envelope detection algorithm. The moving power filter may be comprised of a moving kernel of length that is equal to the average length of an individual ultrasound echo 162. With each iteration of the moving kernel, the power of the RF signal 142 at the instant kernel position is calculated. One exemplary kernel length may be 20 samples; however, other lengths may also be used. The value of the RF signal 142 represents the value of the signal envelope at that position of the RF signal 142. Given a discrete-time signal, X , having a length, N , each envelope, Y , using a moving power filter having length, L , is defined by:

$$Y_k = \sum_{i=k-\frac{L}{2}}^{k+\frac{L}{2}} X_i^2 \forall k \in \left[\frac{L}{2}, N - \frac{L}{2} - 1 \right] \quad (9)$$

5 In some embodiments, this and subsequent equations use a one-sided filter of varying length for the special cases of the samples before the $\frac{L}{2}$ sample (left-sided filter), and after the $N - \frac{L}{2} - 1$ sample (right-sided filter).

10 **[0042]** Each envelope produced by the moving power filter, shown in FIG. 10B, includes a plurality of local peaks (identified in FIG. 10B as enlarged dots at the intersection of each envelope with an echo 162), each being a clear representation of the individual echoes 162 existing in the acquired RF signal 142 for the various tissue interfaces. As an example of such process, FIGS. 12A-12D more clearly illustrate the RF signal 142 (top in each figure) at four iterations of the kernel of the moving power filter as well as the corresponding envelope (bottom in each figure). Individual echoes 162 in each envelope are again identified with an enlarged dot.

15 **[0043]** Of the plurality of echoes 162 in the RF signal 142, one echo 162 is of particular interest, e.g., the echo corresponding to the bone-soft tissue interface. This bone echo (hereafter referenced as 162a) is generated by the reflection of the ultrasound energy at the surface of the scanned bone. More particularly, the soft tissue-bone interface is characterized by a high reflection coefficient of 43%, which means that 43% of the ultrasound energy reaching the surface of the bone is reflected back to the transducer array 68 (FIG. 2) of the ultrasound probe 60 (FIG. 2). This high reflectivity gives bone the characteristic hyper-echoic appearance in an ultrasound image.

20 **[0044]** Bone is also characterized by a high attenuation coefficient of the applied RF signal (6.9 db/cm/mHz for trabecular bone and 9.94 db/cm/mHz for cortical bone). At high frequencies, such as those used in musculoskeletal imaging (that is, in the range of 7-14 MHz), the attenuation of bone becomes very high and the ultrasound energy ends at the surface of the bone. Therefore, an echo 162a corresponding to the soft-tissue-bone interface is the last echo 162a in the RF signal 142. The bone echo 162a is identified by selecting the last echo having a normalized envelope amplitude (with respect to a maximum value existing in the envelope) above a preset threshold (Block 170).

25 **[0045]** The bone echoes 162a are then extracted from each frame 146 (Block 172) and used to generate the bone contour existing in that RF signal 142 and as shown in FIG. 10C (Block 174). In extracting the bone echoes, a probabilistic model (Block 171) may be input and applied to the RF signals 142 of each frame 146. The probabilistic model (Block 171) may further be used in detecting cartilage within the envelopes of the RF signals 142 (Block 173). While the probabilistic signal processing method may include the Bayesian estimator described previously, in still other embodiments, the signal processing may be, a maximum likelihood ratio, neural network, or a support vector machine ("SVM"), for example, with the latter of which is further described below.

30 **[0046]** Prior to implementing the SVM, the SVM may be trained to detect cartilage in RF signals. One such way of training the SVM includes information acquired from a database comprising of MRI images and/or RF ultrasound images to train the SVM to distinguish between echoes associated with cartilage from the RF signals 142, and from within the noise or in ambiguous soft tissue echoes. In constructing the database in accordance with one embodiment, knee joints from multiple patient's are imaged using both MRI and ultrasound. A volumetric MRI image of each knee joint is reconstructed, processed, and the cartilage and the bone tissues are identified and segmented. The segmented volumetric MRI image is then registered with a corresponding segmented ultrasound image (wherein bone tissue is identified). The registration provides a transformation matrix that may then be used to register the raw RF signals 142 with a reconstructed MRI surface model.

35 **[0047]** After the raw RF signals 142 are registered with the reconstructed MRI surface model, spatial information from the volumetric MRI images with respect to the cartilage tissue may be used to determine the location of a cartilage interface on the raw RF signal 142 over the articulating surfaces of the knee joint.

40 **[0048]** The database of all knee joint image pairs (MRI and ultrasound) is then used to train the SVM. Generally, the training includes loading all raw RF signals, as well as the location of the bone-cartilage interface of each respective RF signal. The SVM may then determine the location of the cartilage interface in an unknown, input raw RF signal. If desired, a user may chose from one or more kernels to maximize a classification rate of the SVM.

45 **[0049]** In use, the trained SVM receives a reconstructed knee joint image of a new patient as well as the raw RF signals. The SVM returns the cartilage location on the RF signal data, which may be used, along with the tracking information from the tracking system (i.e., the optical markers 86 and the position sensor 88 (FIGS. 2-2A) are provided herein) to generate 3-D coordinates for each point on the cartilage interface. The 3-D coordinates may be triangulated and interpolated to form a complete cartilage surface.

50 **[0050]** Referring still to FIG. 11, the resultant bone contours may be noisy and require filtering to remove echoes 162 that may be falsely detected as the bone echo 162a. Falsely detected echoes 162 may originate from one of at least two sources: (1) an isolated outlier echoes and (2) a false bone echoes. Furthermore, some images may not include a bone echo 162a; therefore any detected echo 162 is noise and should be filtered out. Therefore, proper determination

of the preset threshold or filtering algorithm may prevent the false selection of a falsely detected echo 162.

[0051] Isolated outliers are those echoes 162 in the RF signal 142 that correspond to a tissue interface that is not the soft-tissue-bone interface. Selection of the isolated outliers may occur when the criterion is set too high. If necessary, the isolated outliers may be removed (Block 176) by applying a median filter to the bone contour. That is, given a particular bone contour, X , having a length, N , with a median filter length, L , the median-filter contour, Y_k , is:

$$Y_k = \text{Median} \left[X_{k-\frac{L}{2}}, X_{k+\frac{L}{2}} \right] \quad \forall k \in \left[\frac{L}{2}, N - \frac{L}{2} - 1 \right] \quad (10)$$

[0052] False bone echoes are those echoes 162 resulting from noise or a scattering echo, which result in a detected bone contour in a position where no bone contour exists. The false bone echoes may occur when an area that does not contain a bone is scanned, the ultrasound probe 60 (FIG. 2) is not oriented substantially perpendicular with respect to the bone surface, the bone lies deeper than a selected scanning depth, the bone lies within the selected scanning depth but its echo is highly attenuated by the soft tissue overlying the bone, or a combination of the same. Selection of the false bone echoes may occur when the preset threshold is too low.

[0053] Frames 146 containing false bone echoes should be removed. One such method of removing the false bone echoes (Block 178) may include applying a continuity criteria. That is, because the surface of the bone has a regular shape, the bone contour, in the two-dimensions of the ultrasound image, should be continuous and smooth. A false bone echo will create a non-continuity, and exhibits a high degree of irregularity with respect to the bone contour.

[0054] One manner of filtering out false bone echoes is to apply a moving standard deviation filter; however, other filtering methods may also be used. For example, given the bone contour, X , having a length, N , with a median filter length, L , the standard deviation filter contour:

$$Y_k = \sqrt{\frac{1}{L-1} \sum_{i=k-\frac{L}{2}}^{i=k+\frac{L}{2}} (X_i - \bar{X})^2} \quad \forall k \in \left[\frac{L}{2}, N - \frac{L}{2} - 1 \right] \quad (11)$$

Where Y_k is the local standard deviation of the bone contour, which is a measure of the regularity and continuity of the bone contour. Segments of the bone contour including a false bone echo are characterized by a higher degree of irregularity and have a high Y_k value. On the other hand, segments of the bone contour including only echoes resulting from the surface of the bone are characterized by high degree regularity and have a low Y_k value.

[0055] A resultant bone contour 180, resulting from applying the moving median filter and the moving standard deviation filter, includes a full length contour of the entire surface of the bone, one or more partial contours of the entire surface, or contains no bone contour segments.

[0056] FIGS. 12A-12F and 13A-13F illustrate the resultant bone contour 180 that is selected from those segments of the extracted bone contour that satisfy two conditions: (1) the continuity criteria, having a local standard deviation value below selected standard deviation threshold and (2) a minimum-length criteria, which avoids piecewise-smooth noise contour segments from being falsely detected as bone contour. In some exemplary embodiments, the length of the standard deviation filter may be set to 3 and the threshold set to 1.16 mm, which may correspond to 30 signal samples. Accordingly, FIGS. 13A and 13D illustrate two exemplary RF signals 142 with the resultant bone contours 180 extracted and filtered from the noise 182 (including isolated outliers and false body echoes), shown in FIGS. 13B and 13E, respectively. FIGS. 13C and 13F respectively illustrate the standard deviation, Y_k , calculated as provided in Equation 11 above. FIGS. 14A-14F are similar to FIGS. 13A-13F, but include two exemplary signals 142 in which no bone tissue was scanned.

[0057] With the bone contours isolated from each of the RF signals, the bone contours may now be transformed into a point cloud. For instance, returning now to FIG. 7, the resultant bone contours 180 may then undergo registration with the optical system to construct a bone point cloud 194 representing the surface of at least a portion of each scanned bone (Block 186), which is described herein as a multiple step registration process. In one embodiment, the process is a two-step registration process. The registration step (Block 186) begins by transforming the resultant bone contour 180 from a 2D contour in the ultrasound frame into a 3-D contour in the world frame (Block 188). This transformation is applied to all resultant bone contours 180 extracted from all of the acquired RF signals 142.

[0058] To transform the resultant bone contour 180 into the 3-D contour, each detected bone echo 162a undergoes transformation into a 3-D point as follows:

$$d_{echo} = n_{echo} T_s C_{us} \quad (12)$$

$$l_{echo} = L_{trans} \frac{n_{line}}{N_{lines}} \hat{u}_x \quad (13)$$

$$P_{echo}^{OP} = P_{trans-origin} + d_{echo} \hat{u}_y + l_{echo} \hat{u}_x \quad (14)$$

$$P_{echo}^W = H_{OP}^W P_{echo}^{OP} \quad (15)$$

10 Where the variables are defined as follows:

	d_{echo}	depth of the bone echo (cm)
	n_{echo}	sample index of the detected bone echo
15	T_s	RF signal sampling period (sec/sample)
	C_{US}	speed of ultrasound in soft tissue (154×10^3 cm/s)
	l_{echo}	distance from the $P_{trans-origin}$ (FIG. 2) of the transducer array 68 (FIG. 2) to the current scan line (cm)
20	P_{echo}^{OP}	detected point on the bone surface represented in the local frame
	n_{line}	index of the scan line containing the bone echo in the image
	N_{lines}	number of scan lines in the image
25	P_{echo}^W	detected surface of the bone relative to the world frame
	H_{OP}^W	homogeneous transformation between the local frame and the world frame, as described previously
30	H_{OP}^W	dynamically obtained transformation that contains the position and orientation of the optical marker 86 (FIG. 2)

[0059] If so desired, an intermediate registration process may be performed between the resultant bone contour and a B-mode image, if acquired (Block 190). This registration step is performed for visualizing the resultant bone contour 180 with the B-mode image (FIG. 9), which provides visual validation and feedback of the resultant bone contour 180 detection process, in real time, while the user is performing the scan. This visual validation may aid the user in determining whether acquisition is completed (Block 160), as described previously. More specifically, the resultant bone contour 180 is registered with the B-mode image by:

$$P_{echo}^l = (l_{echo} l_x \quad d_{echo} l_y) \quad (16)$$

Where l_x and l_y denote the B-mode image resolution (pixels/cm) for the x- and y-axes respectively. P_{echo}^l denotes the coordinates of the bone contour point relative to the ultrasound frame.

[0060] After the resultant bone contours 180 are transformed and, if desired, registered (Block 190) (FIG. 15), the plurality of point clouds 165 (FIG. 16B) are generated representing the surface of the bone. During the second registration process the plurality of point clouds 165 are integrated into a bone point cloud 194 representing the entire surface of the scanned bone.

[0061] To begin the second registration process, as shown in FIGS. 16A-17D, the plurality of point clouds 164 are initially aligned to a standardized model of the scanned bone, here a model femur 200, for example, by using 4-6 previously specified landmarks 196 (Block 192). More specifically, the user may identify the plurality of landmarks 196 on the model femur 200, which need not be identified with high accuracy. After this initial alignment, an iterative closest point ("ICP") alignment is performed to more accurately align the plurality of point clouds to the standardized model. If necessary, noise may be removed by thresholding for a distance between a respective point of the plurality of point clouds and the closest vertices in the model femur 200; however, other filtering methods may alternatively be used. For instance, an average distance plus one standard deviation may be used as the threshold. The process is repeated for each point cloud 165 of the plurality for the surface of the scanned bone.

[0062] The now aligned point clouds 165 are then integrated into a single uniform point cloud 194 that represents the surface of the scanned bone (Block 202).

[0063] After the point clouds 194 are formed, a bone model may be optimized in accordance with the point clouds 194. That is, the bone point cloud 194 is then used to reconstruct a 3-D patient-specific model of the surface of the scanned bone. The reconstruction begins with a determination of a bone model from which the 3-D patient-specific model is derived (Block 210). The bone model may be a generalized model based on multiple patient bone models and may be selected from a principle component analysis ("PCA") based statistical bone atlas. One such *a priori* bone atlas, formed in accordance with the method 212 of FIG. 18, includes a dataset of 400 dry femur and tibia bone pairs, scanned by CT (Block 214) and segmented to create models of each bone (Block 216). The method of building and using one such statistical atlas is described in MAHFOUZ M et al., "Automatic Methods for Characterization of Sexual Dimorphism of Adult Femora: Distal Femur," Computer Methods in Biomechanics and Biomedical Engineering, 10(6) 2007, the disclosure of which is incorporated herein by reference in its entirety.

[0064] Each bone model, M_i , (where $i \in [1, N]$, N being the number of models in the dataset) has the same number of vertices, wherein the vertex, V_j , in a select one model corresponds (at the same anatomical location on the bone) to the vertex, V_j , in another one model within the statistical atlas.

[0065] PCA was then performed on each model in the dataset to extract the modes of variation of the surface of the bone (Block 218). Each mode of variation is represented by a plurality of eigenvectors resulting from the PCA. The eigenvectors, sometimes called eigenbones, define a vector space of bone morphology variations extracted from the dataset. The PCA may include any one model from the dataset, expressed as a linear combination of the eigenbones. An average model of all of the 3-D models comprising the dataset is extracted (Block 220) and may be defined as:

$$M_{avg} = \frac{1}{N} \sum_{i=1}^N M_i \quad (17)$$

$$M_i = M_{avg} + \sum_{k=1}^L \alpha_{ik} U_k \quad \forall i \in [1, N] \quad (18)$$

Where the variables are defined as follows:

M_{avg}	is the mean bone of the dataset
L	dimensionality of the eigenspace (i.e., the number of eigenbones) and is equal to N
N	number of models in the data
U_k	k^{th} eigenbone
α_{ik}	k^{th} shape descriptor or eigenbone's coefficient for the i^{th} model

[0066] Furthermore, any new model, M_{new} , i.e., a model not already existing in the dataset, may be approximately represented by new values of the shape descriptors (eigenvectors coefficients) as follows:

$$M_{new} \simeq M_{avg} + \sum_{k=1}^W \alpha_k U_k \quad (19)$$

Where the variables are defined as follows:

M_{new}	new bone model
α_k	indexed shape descriptors for the new model
W	number of principal components to use in the model approximation, where $W \leq L$

[0067] The accuracy of M_{new} is directly proportional to the number of principal components (W) used in approximating the new model and the number of models, L , of the dataset used for the PCA. The residual error or root mean square error ("RMS") for using the PCA shape descriptors is defined by:

$$RMS = \text{rms} \left[M_{new} - \left(M_{avg} + \sum_{k=1}^W \alpha_k U_k \right) \right] \quad (20)$$

[0068] Therefore, the RMS when comparing any two different models, A and B, having the same number of vertices is defined by:

$$5 \quad \text{RMS} = \text{rms}(A - B) = \sqrt{\frac{\sum_{j=1}^m \|V_{Aj} - V_{Bj}\|^2}{m}} \quad (21)$$

Where V_{Aj} is the j^{th} vertex in model A, and similarly, V_{Bj} is the j^{th} vertex in model B.

[0069] Returning again to FIG. 7, the average model ("AVERAGE" branch of Block 210) is loaded (Block 230) or a subset model is selected ("SELECTED" branch of Block 210) from the statistical atlas based on demographics that are similar to the patient and loaded (Block 232) for optimization. The bone point cloud 194 is then applied to the loaded model (Block 234) so that the shape descriptors of the loaded model may be changed to create the 3-D patient-specific model. If desired, one or more shape descriptors may be constrained ("YES" branch of Block 254) so that the 3-D patient-specific model will have the same anatomical characteristics as the loaded model. Accordingly, the one or more shape descriptors are set (Block 238). With the constraints set, the loaded model may be deformed (or optimized) (Block 240) into a model that resembles the appropriate bone and not an irregularly, randomly shaped model. If no constraints are desired ("NO" branch of Block 240) and then the loaded model is optimized (Block 240).

[0070] Changing the shape descriptors to optimize the loaded model (Block 240) may be carried out by one or more optimization algorithms, guided by a scoring function, to find the values of the principal components coefficients to create the 3-D patient-specific new model and are described with reference to FIG. 19. The illustrated optimization algorithm includes a two-step optimization method of successively-applied algorithms to obtain the 3-D patient-specific model that best fits the bone point cloud 194 as discussed below. Although a two-step method is described, the present invention is not limited to just a two-step optimization method.

[0071] The first algorithm may use a numerical method of searching the eigenspace for optimal shape descriptors. More specifically, the first algorithm may be an iterative method that searches the shape descriptors of the loaded model to find a point that best matches the bone point cloud 194 (Block 250). One such iterative method may include, for example, Powell's conjugate gradient descent method with a RMS as the scoring function. The changes are applied to the shape descriptors of the loaded model by the first algorithm to form a new model, M_{new} , (Block 252) defined by Equation 19. The new model, M_{new} , is then compared with the bone point cloud 194 and the residual error, E , calculated to determine whether a further iterative search is required (Block 254). More specifically, given a bone point cloud, Q , having n points therein, and an average model, M_{avg} , with l vertices, there may be a set of closest vertices, V , in the average model, M_{avg} to the bone point cloud, Q .

$$35 \quad v_i = \underset{v_j \in M}{\text{argmin}} \|v_j - q_i\| \quad \forall i \in [1, n], j \in [1, l] \quad (22)$$

Where v_j is the closest point in the set, V , to q_i in the bone point cloud, Q . An octree may be used to efficiently search for the closest points in M_{new} . The residual error, E , between the new model, M_{new} and the bone point cloud, Q , is then defined as:

$$40 \quad E = \|V - Q\|^2 \quad (23)$$

[0072] With sufficiently high residual error ("YES" branch of Block 254), the method returns to further search the shape descriptors (Block 250). If the residual error is low ("NO" branch of Block 254), then the method proceeds.

[0073] The second algorithm of the two-step method refines the new model derived from the first algorithm by transforming the new model into a linear system of equations in the shape descriptors. The linear system is easily solved by linear system equation, implementing conventional solving techniques, which provide the 3-D patient-specific shape descriptors.

[0074] In continuing with FIG. 19, and to transform the new model into the linear system, the roots of the linear system must be determined (Block 256). More specifically, the first partial derivatives of the residual error, E , with respect to the shape descriptors, α_k , are equal to zero. The error function, Equation 23, may be expressed in terms of the vertices, v_i , of the set, V , and the points, p_i , of the point cloud, Q :

$$55 \quad E = \sum_{i=1}^m \|v_i - q_i\|^2 \quad (24)$$

And may also be expressed in terms of the new model's shape descriptors as:

$$E = \|(V_{avg} + \sum_{k=1}^W a_k U'_k) - Q\|^2 \quad (25)$$

Where V_{avg} is the set of vertices from the loaded model's vertices, which corresponds to the vertices set, V , that contains the closest vertices in the new model, M_{new} that is being morphed to fit the bone point cloud, Q . U'_k is a reduced version of the k^{th} eigenbone, U_k , containing only the set of vertices corresponding to the vertices set, V .

[0075] Combining Equations 24 and 25, E maybe expressed as:

$$E = \sum_{i=1}^m \|(v_{avg,i} + \sum_{k=1}^W a_k u'_{k,i}) - q_i\|^2 \quad (26)$$

Where $v_{avg,i}$ is the i^{th} vertex of V_{avg} . Similarly, $u'_{k,i}$ is the i^{th} vertex of the reduced eigenbone, U'_k .

[0076] The error function may be expanded as:

$$E = \sum_{i=1}^m \left[(x_{avg,i} + \sum_{l=1}^W a_l x_{u',l,i} - x_{q,i})^2 + (y_{avg,i} + \sum_{l=1}^W a_l y_{u',l,i} - y_{q,i})^2 + (z_{avg,i} + \sum_{l=1}^W a_l z_{u',l,i} - z_{q,i})^2 \right] \quad (27)$$

Where $x_{avg,i}$ is the x-coordinate of the i^{th} vertex of the average model, $x_{k,i}$ is the x-coordinate of the i^{th} vertex of the k^{th} eigenbone, and $x_{Q,i}$ is the x-coordinate of the i^{th} point of the point cloud, Q . Similar arguments are applied to the y- and z-coordinates. Calculating the partial derivative of E with respect to each shape descriptor, α_k , yields:

$$\frac{\partial E}{\partial \alpha_k} = 0 \quad \forall \quad k \in [1, W] \quad (28)$$

$$\frac{\partial E}{\partial \alpha_k} = \sum_{i=1}^m \left[2(x_{avg,i} + \sum_{l=1}^W a_l x_{u',l,i} - x_{p,i}) x_{k,i} + 2(y_{avg,i} + \sum_{l=1}^W a_l y_{u',l,i} - y_{p,i}) y_{k,i} + 2(z_{avg,i} + \sum_{l=1}^W a_l z_{u',l,i} - z_{p,i}) z_{k,i} \right] = 0 \quad \forall \quad k \in [1, W] \quad (29)$$

[0077] Recombining the coordinate values into vectors yields:

$$\frac{\partial E}{\partial \alpha_k} = \sum_{i=1}^m \left[(v_{avg,i} \cdot u'_{k,i}) + (\sum_{l=1}^W a_l u'_{l,i}) \cdot u'_{k,i} - q_i \cdot u'_{k,i} \right] = 0 \quad \forall \quad k \in [1, W] \quad (30)$$

[0078] And with rearrangement:

$$\sum_{i=1}^m (\sum_{l=1}^W a_l (u'_{l,i} \cdot u'_{k,i})) = \sum_{i=1}^m [q_i \cdot u'_{k,i} - (v_{avg,i} \cdot u'_{k,i})] \quad (31)$$

[0079] Reformulating Equation 31 into a matrix form provides a linear system of equations in the form of $Ax = B$:

$$\begin{aligned}
 & \sum_{i=1}^m \begin{bmatrix} u'_{1,i} \cdot u'_{1,i} & u'_{2,i} \cdot u'_{1,i} & \cdots & \cdots & u'_{W,i} \cdot u'_{1,i} \\ u'_{1,i} \cdot u'_{2,i} & u'_{2,i} \cdot u'_{2,i} & \cdots & \cdots & u'_{W,i} \cdot u'_{2,i} \\ \vdots & \vdots & \ddots & \ddots & \vdots \\ \vdots & \vdots & \ddots & \ddots & \vdots \\ u'_{1,i} \cdot u'_{W,i} & u'_{2,i} \cdot u'_{W,i} & \cdots & \cdots & u'_{W,i} \cdot u'_{W,i} \end{bmatrix} \begin{bmatrix} a_1 \\ a_2 \\ \vdots \\ \vdots \\ a_W \end{bmatrix} = \\
 & \sum_{i=1}^m \begin{bmatrix} (q_i - v_{avg,i}) \cdot u'_{1,i} \\ (q_i - v_{avg,i}) \cdot u'_{2,i} \\ \vdots \\ \vdots \\ (q_i - v_{avg,i}) \cdot u'_{W,i} \end{bmatrix} \quad (32)
 \end{aligned}$$

[0080] The linear system of equations may be solved using any number of known methods, for instance, singular value decomposition (Block 258).

[0081] In one embodiment, the mahalanobis distance is omitted because the bone point clouds are dense, thus providing a constraining force on the model deformation. Therefore the constraining function of the mahalanobis distance may not be needed, but rather was avoided to provide the model deformation with more freedom to generate a new model that best fit the bone point cloud.

[0082] An ultrasound procedure in accordance with the embodiments of the present invention may, for example, generate approximately 5000 ultrasound images. The generated 3-D patient-specific models (Block 260, FIG. 7), when compared against CT-based segmented models, yielded an average error of approximately 2 mm.

[0083] The solution to the linear set of equations provides a description of the patient-specific 3-D model, derived from an average, or select model, from the statistical atlas, and optimized in accordance with the point cloud transformed from a bone contour that was isolated from a plurality of RF signals. The solution may be applied to the average model to display a patient-specific 3-D bone model for aiding in pre-operative planning, mapping out injection points, planning a physical therapy regiment, or other diagnostic and/or treatment-based procedure that involves a portion of the musculoskeletal system.

[0084] Cartilage 3-D models may be reconstructed by a method that is similar to that which was outlined above for bone. During contour extraction, the contour of the cartilage is more difficult to detect than bone. Probabilistic modeling (Block 171) is used to process the raw RF signal to more easily identify cartilage, and SVM aids in detection of cartilage boundaries (Block 173) based on MRI training sets. A cartilage statistical atlas is formed by a method that may be similar to what was described for bone; however, as indicated previously, MRI is used rather than the CT (which was the case for bone). The segmentation (Block 216), variation extraction (Block 218) and base model morphing (Block 240) (FIG. 19) are processed to produce a reconstructed cartilage model in the same manner as a bone model is reconstructed. The cartilage model may be displayed alone, or in conjunction with the 3D patient-specific bone model.

[0085] While the present invention has been illustrated by the description of the embodiments thereof, and while the embodiments have been described in considerable detail, it is not the intention of the applicant to restrict or in any way limit the scope of the appended claims to such detail. Additional advantages and modifications will readily appear to those skilled in the art. Therefore, the present invention in its broader aspects is not limited to the specific details representative apparatus and method, and illustrative examples shown and described. Accordingly, departures may be made from such details, within the scope of the appended claims.

Claims

1. A method of generating a 3-D patient-specific musculoskeletal model, the method comprising:

- acquiring a plurality of raw radio frequency ("RF") signals (142) from an A-mode ultrasound scan of a bone (116, 118, 120, 200);
- tracking the acquiring of the plurality of RF signals in 3-D space and generating tracked data;
- isolating a bone contour (180) from each of the plurality of RF signals (142);
- transforming the bone contours into a point cloud (194) using the tracked data; and
- optimizing a 3-D bone model of the bone with respect to the point cloud (194);

wherein isolating the bone contour further comprises:

sampling each of the plurality of RF signals; and
identifying a bone echo in each sample;

5 wherein the 3-D bone model of the bone is an average bone model of a plurality of bone models in a statistical atlas; and
wherein optimizing the 3-D bone model of the bone further comprises:

comparing the 3-D bone model with the point cloud (194); and
based on the comparing, deforming the 3-D bone model to match the point cloud (194).

10 2. The method of claim 1, wherein acquiring the plurality of RF signals includes moving an ultrasound probe (60), and
tracking the acquiring of the plurality of RF signals in 3-D space comprises tracking with an optical position tracking
system, an electromagnetic position tracking system, or a radiofrequency position tracking system.

15 3. The method of claim 2, wherein tracking the acquiring of the plurality of RF signals in 3-D space comprises tracking
with an optical position tracking system comprising an optical marker and an optical position sensor, wherein the
optical marker includes at least four optical marker points and the optical position sensor is configured to triangulate
a location of the optical mark from the at least four optical marker points.

20 4. The method of claim 1, further comprising:
isolating the bone contour by removing any portions of the bone echo in each sample that deviate from a continuous
contour.

5. The method of claim 1, wherein transforming the bone contours into the point cloud further comprises:

25 transforming the bone contours from a local frame of reference into a world frame of reference; and
integrating the transformed bone contours to form a 3-D bone contour.

6. The method of claim 1, wherein the comparing and deforming are iteratively performed until the comparing results
in a deviation that is less than a deviation threshold.

30 7. The method of claim 1, wherein the 3-D patient-specific musculoskeletal model includes a model of a bone, a model
of a joint, a model of cartilage, or combination thereof.

8. A computing device (54) for generating a 3-D patient-specific musculoskeletal model comprising:

35 a processor (78); and
a memory (80),

40 wherein the memory includes instructions that, when executed by the processor, cause the processor to:

isolate a bone contour from each of a plurality of raw radio frequency ("RF") signals acquired from an A-mode
ultrasound scan of a bone (116, 118, 120, 200) and tracked data generated by tracking the acquisition of the
plurality of RF signals in 3-D space;

45 transform the bone contours into a point cloud (194) using the tracked data; and

optimize a 3-D bone model of the bone with respect to the point cloud (194);

wherein isolating the bone contour further comprises:

50 sampling each of the plurality of RF signals; and
identifying a bone echo in each sample;

wherein the 3-D bone model of the bone is an average bone model of a plurality of bone models in a statistical atlas; and
wherein optimizing the 3-D bone model of the bone further comprises:

55 comparing the 3-D bone model with the point cloud (194); and
based on the comparing, deforming the 3-D bone model to match the point cloud (194).

9. The computing device of claim 8, wherein the memory includes instructions that, when executed by the processor,

cause the processor to:

isolate the bone contour by removing any portions of the bone echo in each sample that deviate from a continuous contour.

- 5 10. The computing device of claim 8, wherein the memory includes instructions that, when executed by the processor, cause the processor to transform the bone contours into the point cloud further comprising:

transforming the bone contours from a local frame of reference into a world frame of reference; and
integrating the transformed bone contours to form a 3-D bone contour.

- 10 11. The computing device of claim 8, wherein the memory includes instructions that, when executed by the processor, cause the processor to iteratively perform the comparing and deforming until the comparing results in a deviation that is less than a deviation threshold.

- 15 12. The computing device of claim 8, wherein the 3-D patient-specific musculoskeletal model includes a model of a bone, a model of a joint, a model of cartilage, or combination thereof.

13. An ultrasound instrument for generating a 3-D patient-specific musculoskeletal model comprising:

20 the computing device of any one of claims 8 to 12;
an ultrasound probe (60) for acquiring a plurality of raw radio frequency ("RF") signals (142) from an A-mode ultrasound scan of a bone (116, 118, 120, 200); and
a 3-D tracking system for tracking the acquiring of the plurality of RF signals in 3-D space and generating tracked data.

- 25 14. The ultrasound instrument of claim 13, wherein the memory includes instructions that, when executed by the processor, cause the processor to:

30 acquire the plurality of RF signals including by moving the ultrasound probe (60), and
wherein the 3-D tracking system comprises an optical position tracking system, an electromagnetic position tracking system, or a radiofrequency position tracking system.

- 35 15. The ultrasound instrument of claim 14, wherein the 3-D tracking system comprises the optical position tracking system and the memory includes instructions that, when executed by the processor, cause the processor to:
track the acquiring of the plurality of RF signals in 3-D space with the optical position tracking system, and the optical position tracking system comprises an optical marker and an optical position sensor, wherein the optical marker includes at least four optical marker points and the optical position sensor is configured to triangulate a location of the optical mark from the at least four optical marker points.

40 **Patentansprüche**

1. Verfahren zum Erzeugen eines patientenspezifischen muskuloskelettalen 3D-Modells, das Verfahren umfassend:

45 Erfassen einer Vielzahl von rohen Hochfrequenzsignalen (radio frequency signals, HF-Signale) (142) aus einer A-Mode-Ultraschalluntersuchung eines Knochens (116, 118, 120, 200);
Verfolgen der Erfassung der Vielzahl von HF-Signalen im 3D-Raum und Erzeugen von verfolgten Daten;
Isolieren einer Knochenkontur (180) aus jedem der Vielzahl von HF-Signalen (142);
Transformieren der Knochenkonturen in eine Punktwolke (194) unter Verwendung der verfolgten Daten; und
50 Optimieren eines 3D-Knochenmodells des Knochens in Bezug auf die Punktwolke (194);
wobei ein Isolieren der Knochenkontur ferner Folgendes umfasst:

55 Abtasten von jedem der Vielzahl von HF-Signalen; und
Identifizieren eines Knochenechos in jeder Probe;

wobei das 3D-Knochenmodell des Knochens ein durchschnittliches Knochenmodell einer Vielzahl von Knochenmodellen in einem statistischen Atlas ist; und
wobei ein Optimieren des 3D-Knochenmodells des Knochens ferner Folgendes umfasst: Vergleichen des 3D-

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Knochenmodells mit der Punktwolke (194); und
basierend auf dem Vergleichen ein Verformen des 3D-Knochenmodells zum Anpassen an die Punktwolke (194).

- 5 **2.** Verfahren nach Anspruch 1, wobei ein Erfassen der Vielzahl von HF-Signalen ein Bewegen einer Ultraschallsonde (60) beinhaltet, und
ein Verfolgen des Erfassens der Vielzahl von HF-Signalen in einem 3D-Raum ein Verfolgen mit einem optischen Positionsverfolgungssystem, einem elektromagnetischen Positionsverfolgungssystem oder einem Hochfrequenz-Positionsverfolgungssystem umfasst.
- 10 **3.** Verfahren nach Anspruch 2, wobei ein Verfolgen der Erfassung der Vielzahl von HF-Signalen in einem 3D-Raum ein Verfolgen mit einem optischen Positionsverfolgungssystem umfasst, das einen optischen Marker und einen optischen Positionssensor umfasst, wobei der optische Marker mindestens vier optische Markierungspunkte beinhaltet und der optische Positionssensor konfiguriert ist, um eine Position der optischen Markierung aus den mindestens vier optischen Markierungspunkten zu triangulieren.
- 15 **4.** Verfahren nach Anspruch 1, ferner umfassend:
Isolieren der Knochenkontur durch Entfernen aller Teile des Knochenechos in jeder Probe, die von einer kontinuierlichen Kontur abweichen.
- 20 **5.** Verfahren nach Anspruch 1, wobei ein Transformieren der Knochenkonturen in die Punktwolke Folgendes umfasst:
Transformieren der Knochenkonturen von einem lokalen Bezugsrahmen in einen weltweiten Bezugsrahmen;
und
Integrieren der transformierten Knochenkonturen zu einer 3D-Knochenkontur.
- 25 **6.** Verfahren nach Anspruch 1, wobei das Vergleichen und Verformen iterativ ausgeführt wird, bis das Vergleichen in einer Abweichung resultiert, die kleiner als ein Abweichungsschwellenwert ist.
- 30 **7.** Verfahren nach Anspruch 1, wobei das patientenspezifische muskuloskelettale 3D-Modell ein Modell eines Knochens, ein Modell eines Gelenks, ein Modell eines Knorpels oder eine Kombination davon beinhaltet.
- 35 **8.** Rechenvorrichtung (54) zum Erzeugen eines patientenspezifischen muskuloskelettalen 3D-Modells, umfassend:
einen Prozessor (78); und
einen Speicher (80),
wobei der Speicher Anweisungen beinhaltet, die, wenn sie durch den Prozessor ausgeführt werden, den Prozessor zu Folgendem veranlassen:
Isolieren einer Knochenkontur von jeder von einer Vielzahl von rohen Hochfrequenzsignalen (radio frequency signals, HF-Signale), die aus einer A-Mode-Ultraschalluntersuchung (116, 118, 120, 200) und verfolgten Daten, die durch Verfolgen der Erfassung der Vielzahl von HF-Signalen in einem 3D-Raum erzeugt wurden, erfasst werden;
Transformieren der Knochenkonturen in eine Punktwolke (194) unter Verwendung der verfolgten Daten;
und Optimieren eines 3D-Knochenmodells des Knochens in Bezug auf die Punktwolke (194);
- 40 wobei ein Isolieren der Knochenkontur ferner Folgendes umfasst:
Abtasten jedes der Vielzahl von HF-Signalen; und
Identifizieren eines Knochenechos in jeder Probe;
- 45 wobei das 3D-Knochenmodell des Knochens ein durchschnittliches Knochenmodell einer Vielzahl von Knochenmodellen in einem statistischen Atlas ist; und
wobei ein Optimieren des 3D-Knochenmodells des Knochens ferner Folgendes umfasst:
- 50 Vergleichen des 3D-Knochenmodells mit der Punktwolke (194); und
basierend auf dem Vergleichen, Verformen des 3D-Knochenmodells, um der Punktwolke (194) zu entsprechen.
- 55

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9. Rechenvorrichtung nach Anspruch 8, wobei der Speicher Anweisungen beinhaltet, die, wenn sie durch den Prozessor ausgeführt werden, den Prozessor zu Folgendem veranlassen:
Isolieren der Knochenkontur durch Entfernen aller Teile des Knochenechos in jeder Probe, die von einer kontinuierlichen Kontur abweichen.

5

10. Computervorrichtung nach Anspruch 8, wobei der Speicher Anweisungen beinhaltet, die, wenn sie durch den Prozessor ausgeführt werden, den Prozessor veranlassen, die Knochenkonturen in die Punktwolke zu transformieren; ferner umfassend:

10 Transformieren der Knochenkonturen von einem lokalen Bezugsrahmen in einen weltweiten Bezugsrahmen;
und
Integrieren der transformierten Knochenkonturen zu einer 3D-Knochenkontur.

11. Rechenvorrichtung nach Anspruch 8, wobei der Speicher Anweisungen beinhaltet, die, wenn sie durch den Prozessor ausgeführt werden, den Prozessor veranlassen, das Vergleichen und Verformen iterativ auszuführen, bis das Vergleichen in einer Abweichung resultiert, die kleiner als ein Abweichungsschwellenwert ist.

15

12. Rechenvorrichtung nach Anspruch 8, wobei das patientenspezifische muskuloskelettale 3D-Modell ein Modell eines Knochens, ein Modell eines Gelenks, ein Modell eines Knorpels oder eine Kombination davon beinhaltet.

20

13. Ultraschallinstrument zum Erzeugen eines patientenspezifischen muskuloskelettalen 3D-Modells, umfassend:

Rechenvorrichtung nach einem der Ansprüche 8 bis 12;
eine Ultraschallsonde (60) zum Erfassen einer Vielzahl von rohen Hochfrequenzsignalen (radio frequency signals, HF-Signale) (142) aus einer A-Mode-Ultraschalluntersuchung eines Knochens (116, 118, 120, 200); und
ein 3D-Verfolgungssystem zum Verfolgen der Erfassung der Vielzahl von HF-Signalen in einem 3D-Raum und Erzeugen von verfolgten Daten.

25

14. Ultraschallinstrument nach Anspruch 13, wobei der Speicher Anweisungen beinhaltet, die, wenn sie durch den Prozessor ausgeführt werden, den Prozessor zu Folgendem veranlassen:

30

Erfassen der Vielzahl von HF-Signalen, einschließlich durch Bewegen der Ultraschallsonde (60), und wobei das 3D-Verfolgungssystem ein optisches Positionsverfolgungssystem, ein elektromagnetisches Positionsverfolgungssystem oder ein Hochfrequenz-Positionsverfolgungssystem umfasst.

35

15. Ultraschallgerät nach Anspruch 14, wobei das 3D-Verfolgungssystem das optische Positionsverfolgungssystem umfasst und der Speicher Anweisungen beinhaltet, die, wenn sie durch den Prozessor ausgeführt werden, den Prozessor zu Folgendem veranlassen:

40

Verfolgen der Erfassung der Vielzahl von HF-Signalen in einem 3D-Raum mit dem optischen Positionsverfolgungssystem, und wobei das optische Positionsverfolgungssystem einen optischen Marker und einen optischen Positionssensor umfasst, wobei der optische Marker mindestens vier optische Markierungspunkte beinhaltet und der optische Positionssensor konfiguriert ist, um eine Position der optischen Markierung aus den mindestens vier optischen Markierungspunkten zu triangulieren.

45

Revendications

1. Procédé de génération d'un modèle musculo-squelettique 3D spécifique au patient, le procédé comprenant :

l'acquisition d'une pluralité de signaux radio-fréquence (« RF ») bruts (142) à partir d'une numérisation ultrason en mode A d'un os (116, 118, 120, 200) ;
le suivi de l'acquisition de la pluralité de signaux RF dans l'espace 3D et la génération de données suivies ;
l'isolement d'un contour d'os (180) à partir de chacun de la pluralité de signaux RF (142) ; la transformation des contours d'os en un nuage de points (194) en utilisant les données suivies ; et l'optimisation d'un modèle d'os en 3D de l'os par rapport au nuage de points (194) ;
dans lequel l'isolement du contour d'os comprend en outre :

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l'échantillonnage de chacun de la pluralité de signaux RF ;

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et l'identification d'un écho d'os dans chaque échantillon ;
dans lequel le modèle d'os en 3D de l'os est un modèle d'os moyen d'une pluralité de modèles d'os dans
un atlas statistique ; et
dans lequel l'optimisation du modèle d'os en 3D de l'os comprend en outre :
la comparaison du modèle d'os en 3D au nuage de points (194) ; et sur la base de la comparaison, la
déformation du modèle d'os en 3D pour correspondre au nuage de points (194).

2. Procédé selon la revendication 1, dans lequel l'acquisition de la pluralité de signaux RF inclut le déplacement d'une
sonde ultrason (60), et le suivi de l'acquisition de la pluralité de signaux RF dans l'espace 3D comprend le suivi
avec un système de suivi de position optique, un système de suivi de position électromagnétique, ou un système
de suivi de position radio-fréquence.

3. Procédé selon la revendication 2, dans lequel le suivi de l'acquisition de la pluralité de signaux RF dans l'espace
3D comprend le suivi avec un système de suivi de position optique comprenant un marqueur optique et un capteur
de position optique, dans lequel le marqueur optique inclut au moins quatre points marqueurs optiques et le capteur
de position optique est configuré pour trianguler une localisation de la marque optique à partir des au moins quatre
points marqueurs optiques.

4. Procédé selon la revendication 1, comprenant en outre :

l'isolement du contour d'os en retirant toute partie de l'écho d'os dans chaque échantillon qui dévie d'un contour
continu.

5. Procédé selon la revendication 1, dans lequel la transformation des contours d'os dans le nuage de points comprend
en outre :

la transformation des contours d'os depuis un cadre de référence local vers un cadre de référence mondial ; et
l'intégration des contours d'os transformés pour former un contour d'os en 3D.

6. Procédé selon la revendication 1, dans lequel la comparaison et la déformation sont exécutées de manière itérative
jusqu'à ce que la comparaison résulte en une déviation qui est inférieure à un seuil de déviation.

7. Procédé selon la revendication 1, dans lequel le modèle musculo-squelettique 3D spécifique au patient inclut un
modèle d'os, un modèle d'articulation, un modèle de cartilage, ou une combinaison de ceux-ci.

8. Dispositif informatique (54) destiné à générer un modèle musculo-squelettique 3D spécifique au patient comprenant :

un processeur (78) ; et une mémoire (80), dans lequel la mémoire inclut des instructions qui, lorsqu'elles sont
exécutées par le processeur, amènent le processeur à :

isoler un contour d'os à partir de chacun d'une pluralité de signaux radio-fréquence (« RF ») bruts acquis à
partir d'une numérisation ultrason en mode A d'un os (116, 118, 120, 200) et de données suivies générées par
le suivi de l'acquisition de la pluralité de signaux RF dans l'espace 3D ; transformer les contours d'os dans un
nuage de points (194) en utilisant les données suivies ; et optimiser un modèle d'os en 3D de l'os par rapport
au nuage de points (194) ;

dans lequel l'isolement du contour d'os comprend en outre :

l'échantillonnage de chacun de la pluralité de signaux RF ; et l'identification d'un écho d'os dans chaque
échantillon ;

dans lequel le modèle d'os en 3D de l'os est un modèle d'os moyen d'une pluralité de modèles d'os dans
un atlas statistique ; et

dans lequel l'optimisation du modèle d'os en 3D de l'os comprend en outre :

la comparaison du modèle d'os en 3D au nuage de points (194) ; et

sur la base de la comparaison, la déformation du modèle d'os en 3D pour correspondre au nuage de
points (194).

9. Dispositif informatique selon la revendication 8, dans lequel la mémoire inclut des instructions qui, lorsqu'elles sont
exécutées par le processeur, amènent le processeur à :

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isoler le contour d'os en retirant toute partie de l'écho d'os dans chaque échantillon qui dévie d'un contour continu.

- 5 10. Dispositif informatique selon la revendication 8, dans lequel la mémoire inclut des instructions qui, lorsqu'elles sont exécutées par le processeur, amènent le processeur à transformer les contours d'os dans le nuage de points comprenant en outre :

la transformation des contours d'os depuis un cadre de référence local vers un cadre de référence mondial ; et l'intégration des contours d'os transformés pour former un contour d'os en 3D.

- 10 11. Dispositif informatique selon la revendication 8, dans lequel la mémoire inclut des instructions qui, lorsqu'elles sont exécutées par le processeur, amènent le processeur à exécuter de manière itérative la comparaison et la déformation jusqu'à ce que la comparaison résulte en une déviation qui est inférieure à un seuil de déviation.

- 15 12. Dispositif informatique selon la revendication 8, dans lequel le modèle musculo-squelettique 3D spécifique au patient inclut un modèle d'un os, un modèle d'une articulation, un modèle de cartilage, ou une combinaison de ceux-ci.

13. Instrument ultrason destiné à générer un modèle musculo-squelettique 3D spécifique au patient comprenant :

20 le dispositif informatique selon l'une quelconque des revendications 8 à 12 ;
une sonde ultrason (60) destinée à acquérir une pluralité de signaux radio-fréquence (« RF ») bruts (142) à partir d'une numérisation ultrason en mode A d'un os (116, 118, 120, 200) ; et un système de suivi 3D destiné à suivre l'acquisition de la pluralité de signaux RF dans l'espace 3D et à générer des données suivies.

- 25 14. Instrument ultrason selon la revendication 13, dans lequel la mémoire inclut des instructions qui, lorsqu'elles sont exécutées par le processeur, amènent le processeur à :
acquérir la pluralité de signaux RF en incluant le déplacement d'une sonde ultrason (60), et dans lequel le système de suivi 3D comprend un système de suivi de position optique, un système de suivi position électromagnétique ou un système de suivi de position radiofréquence.

- 30 15. Instrument ultrason selon la revendication 14, dans lequel le système de suivi 3D comprend le système de suivi de position optique et la mémoire inclut des instructions qui, lorsqu'elles sont exécutées par le processeur, amènent le processeur à :
suivre l'acquisition de la pluralité de signaux RF dans l'espace 3D avec le système de suivi de position optique, et le système de suivi de position optique comprend un marqueur optique et un capteur de position optique, dans
35 lequel le marqueur optique inclut au moins quatre points marqueurs optiques et le capteur de position optique est configuré pour trianguler une localisation de la marque optique à partir des au moins quatre points marqueurs optiques.

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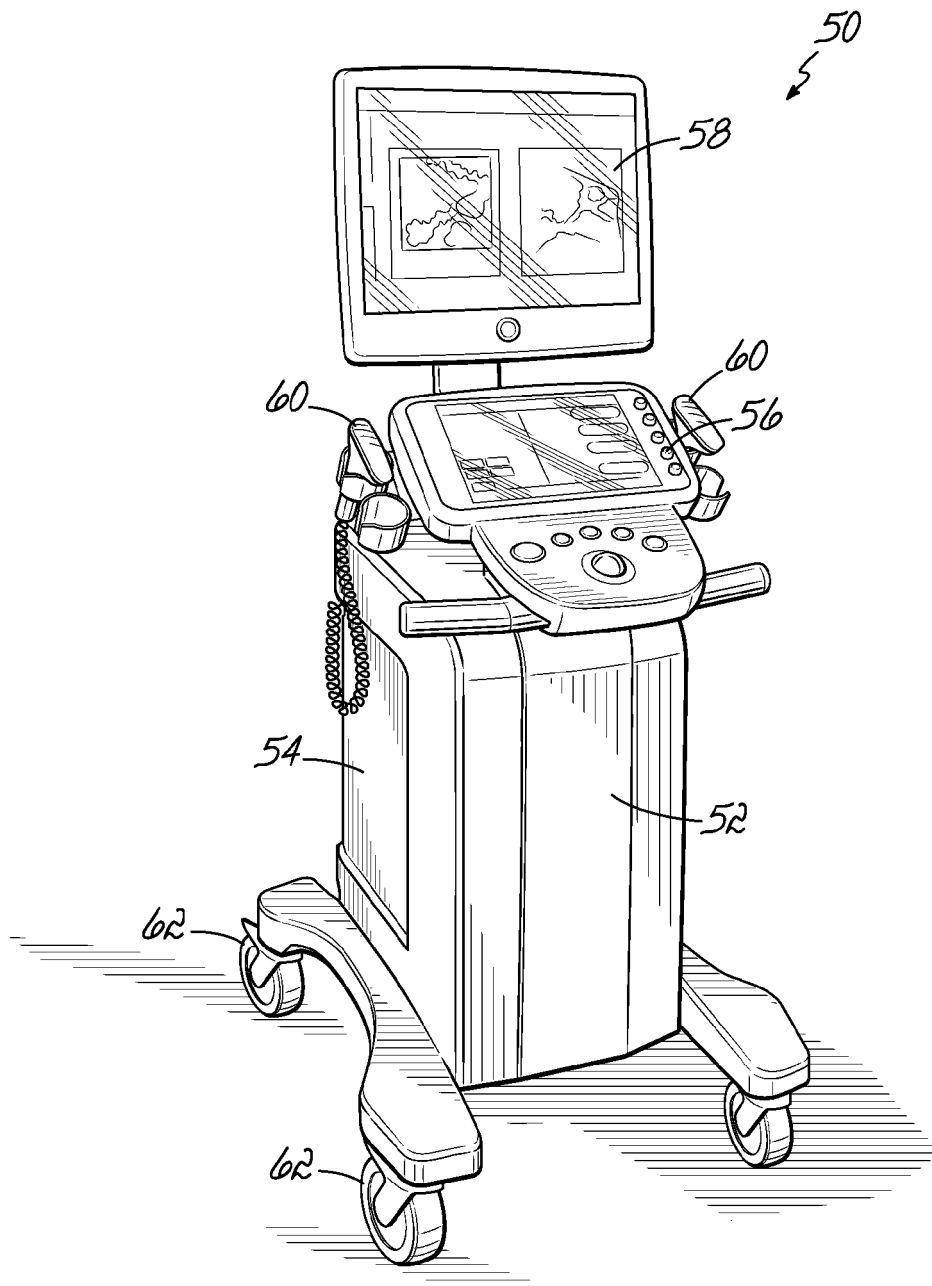


FIG. 1

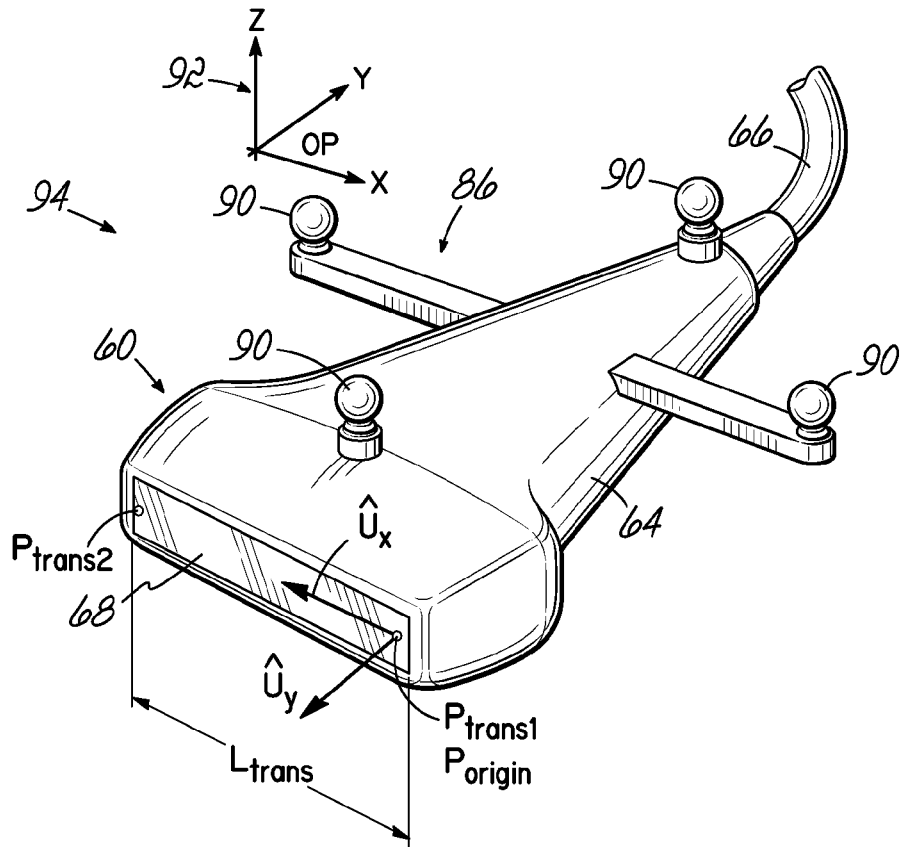


FIG. 2

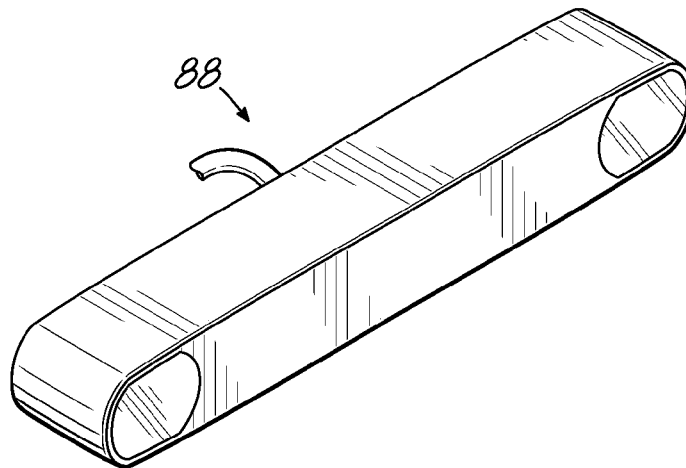


FIG. 2A

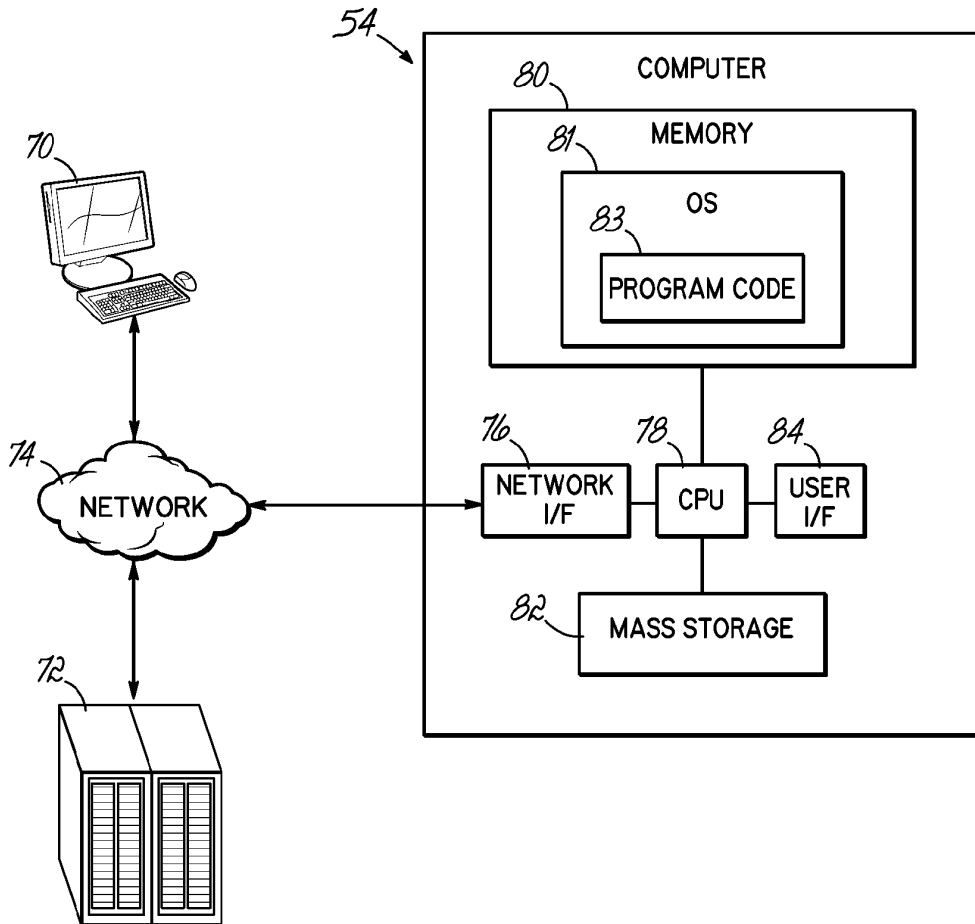


FIG. 3

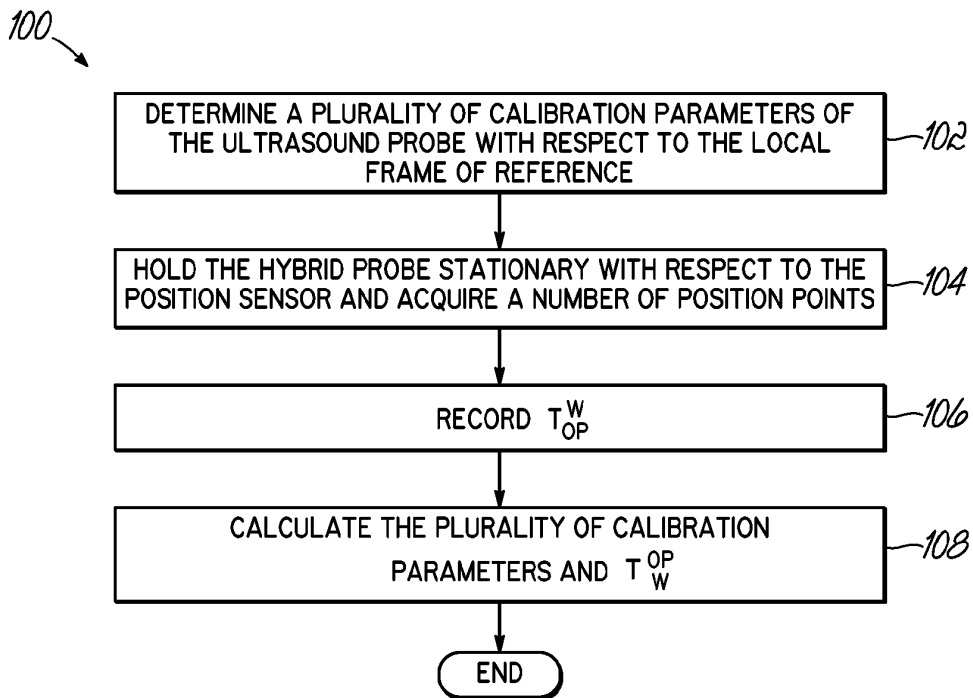


FIG. 4

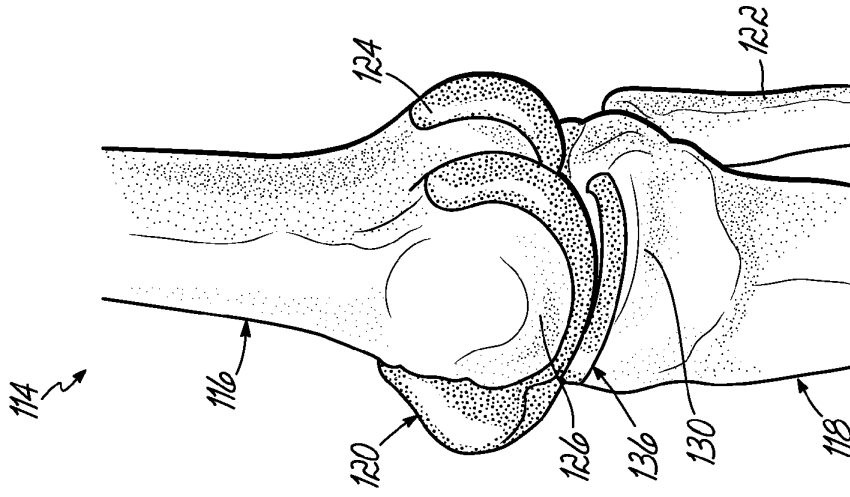


FIG. 5A

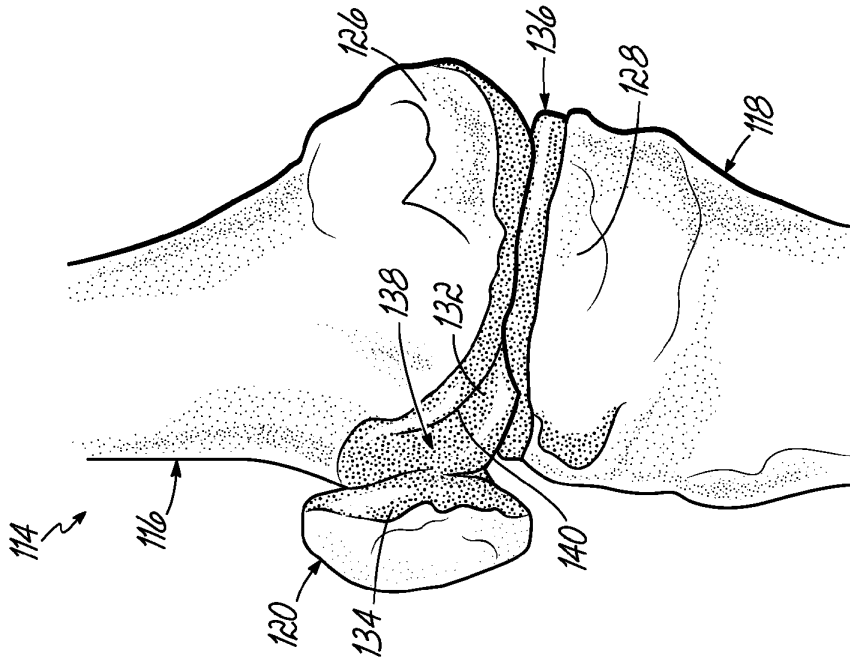


FIG. 5B

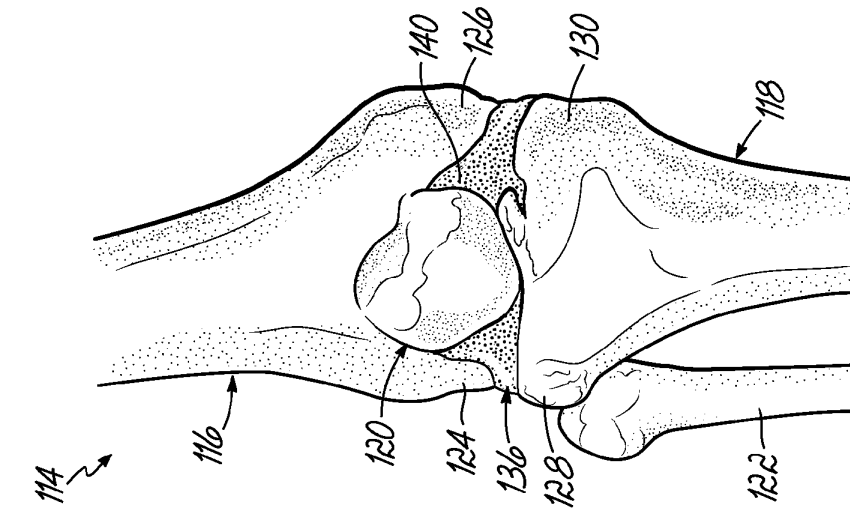


FIG. 5C

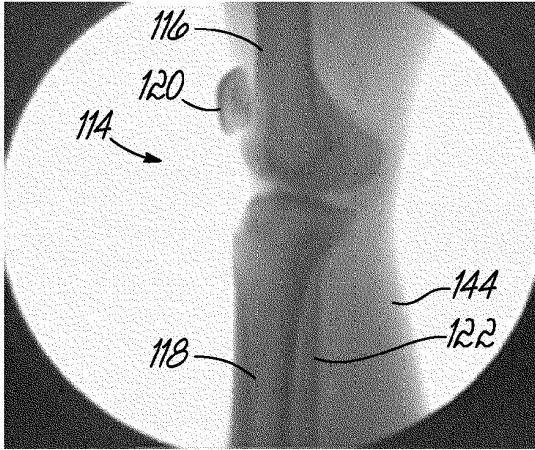


FIG. 6A

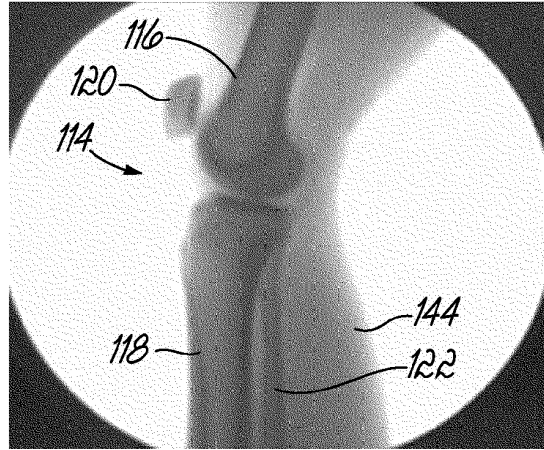


FIG. 6B

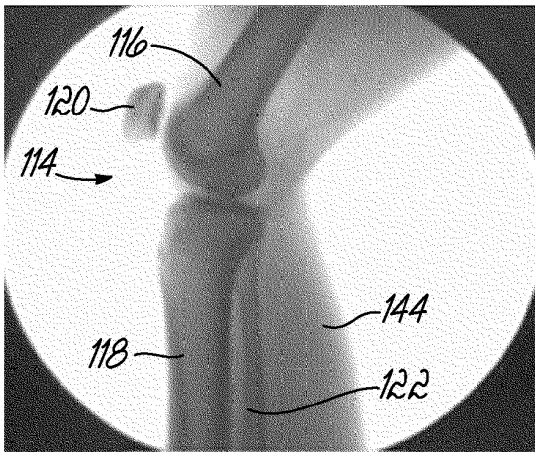


FIG. 6C

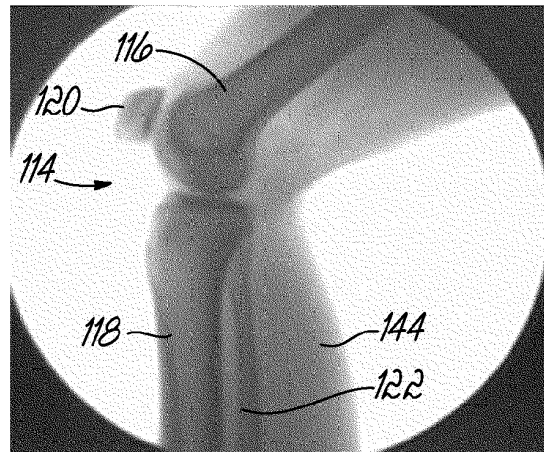


FIG. 6D

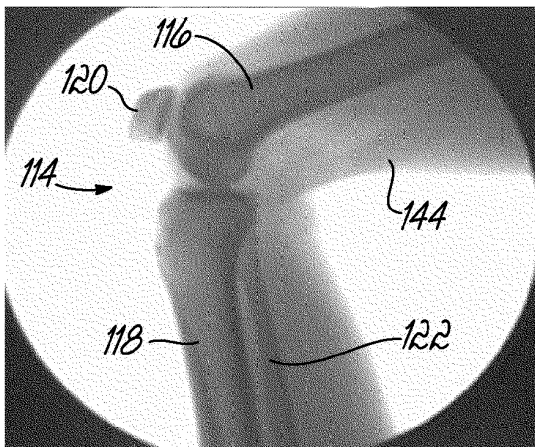


FIG. 6E

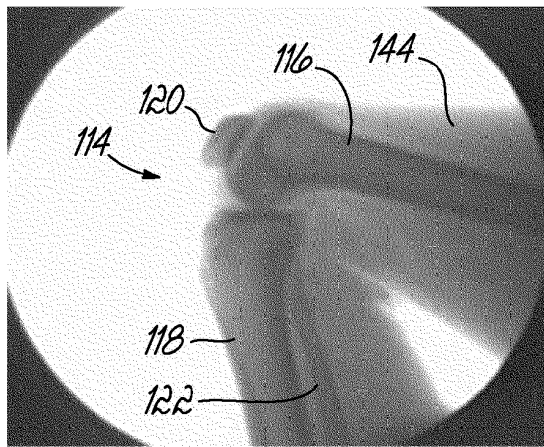


FIG. 6F

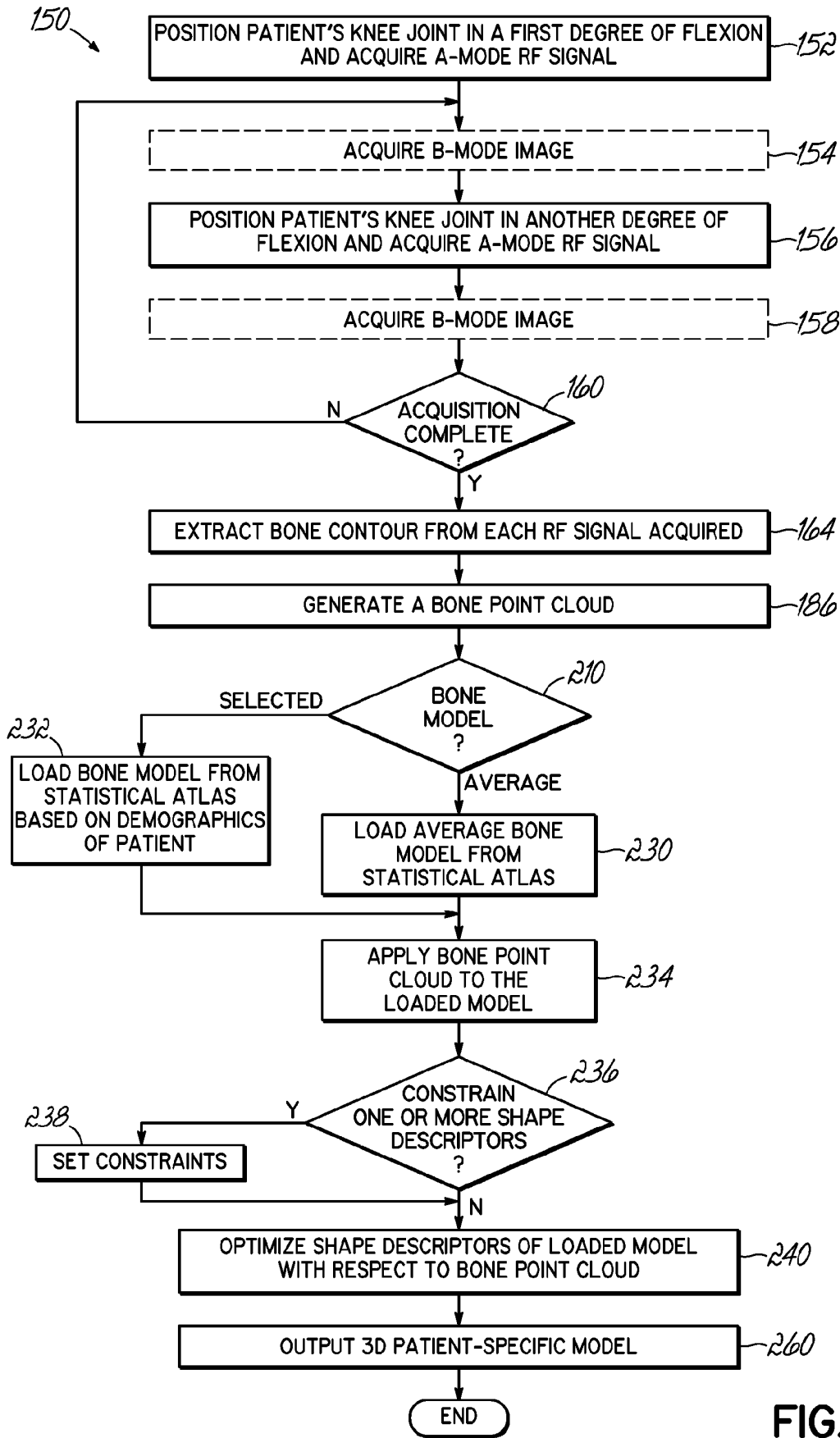


FIG. 7

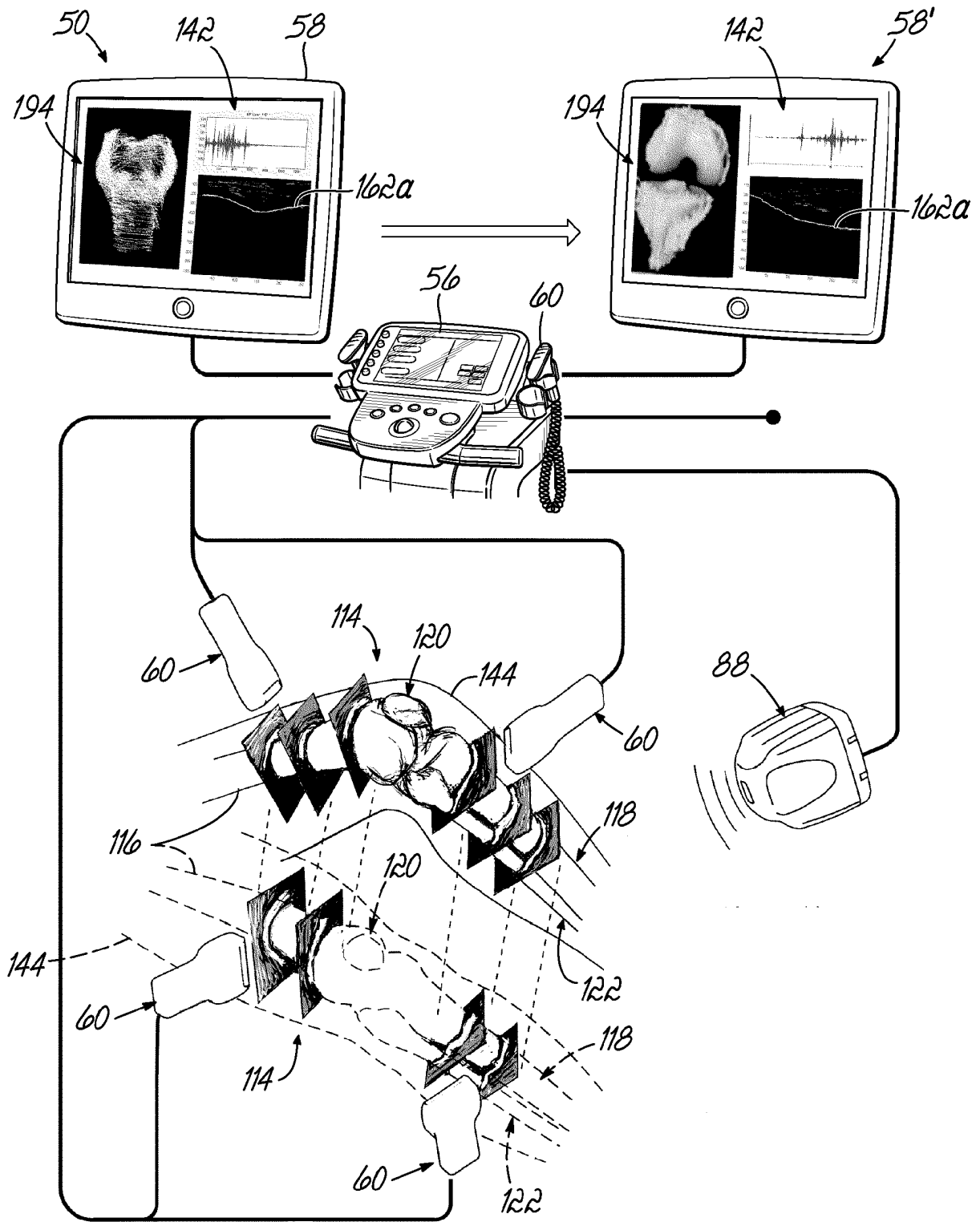


FIG. 8

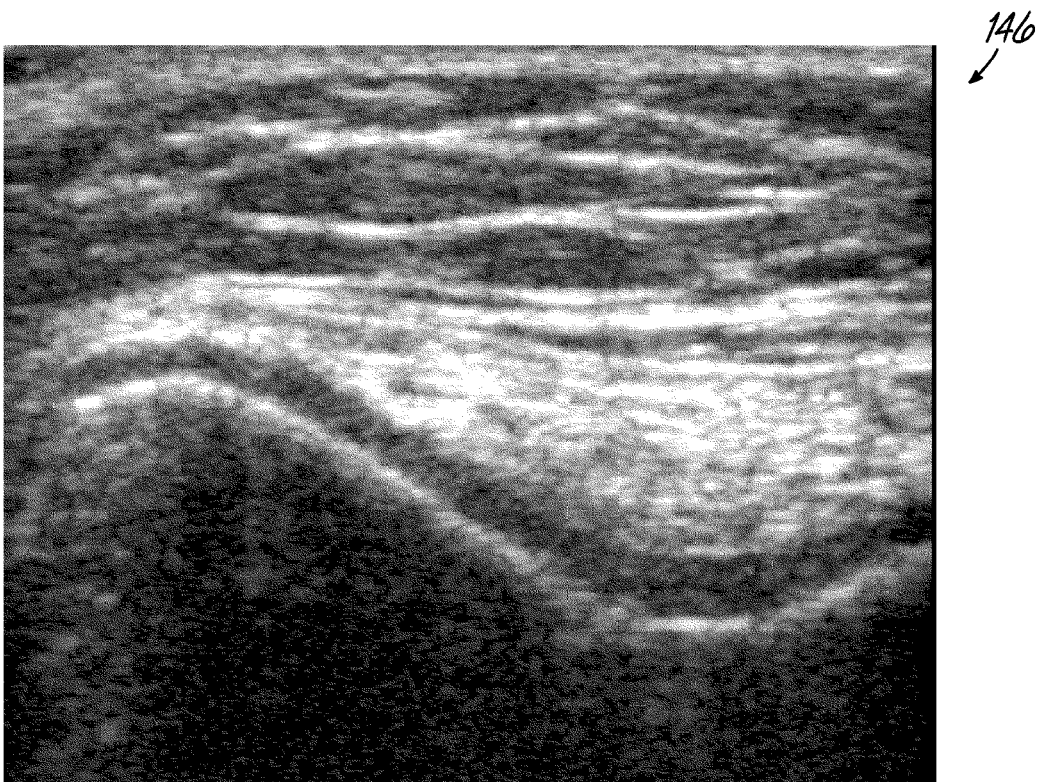


FIG. 9

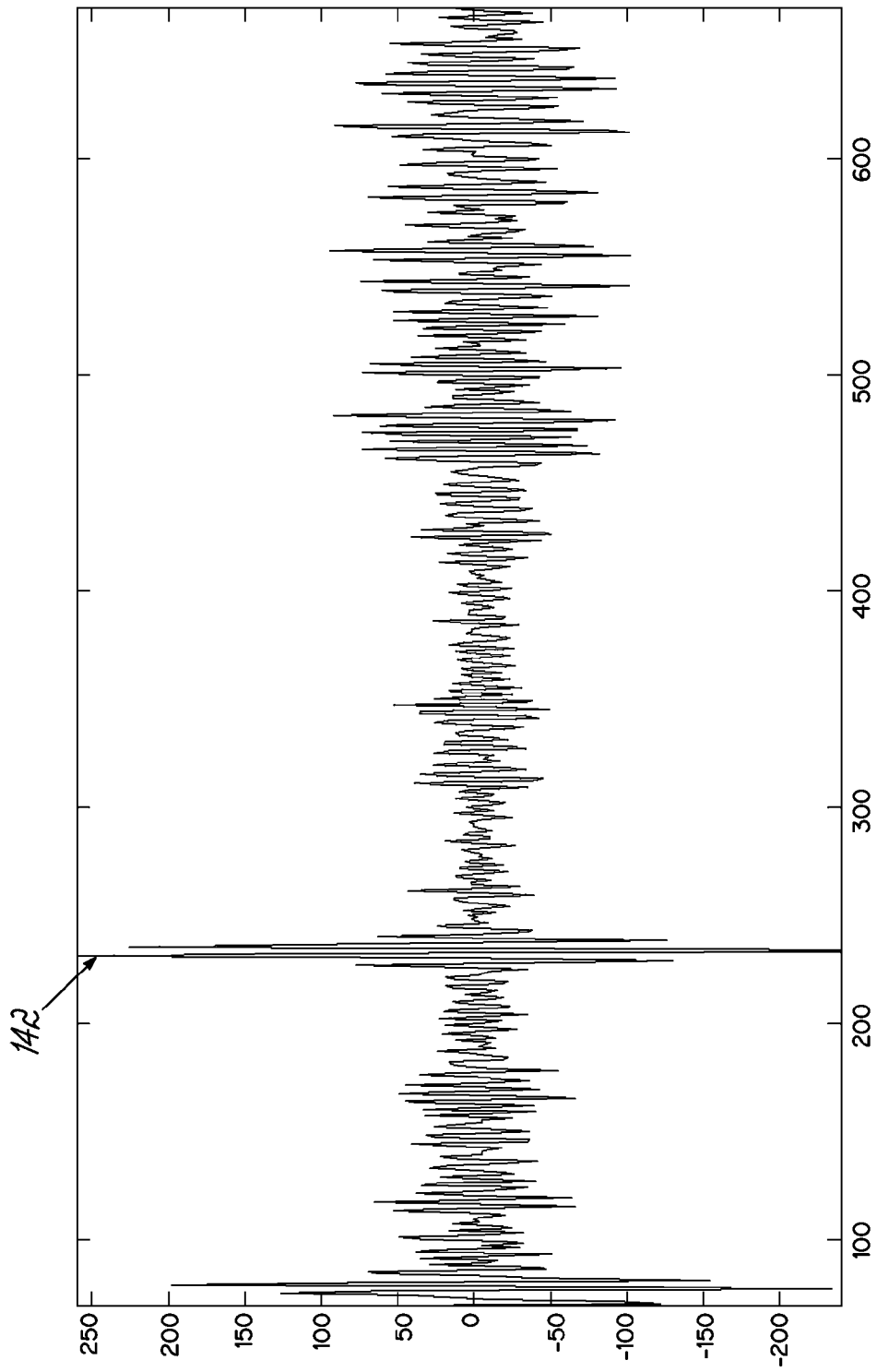


FIG. 10A

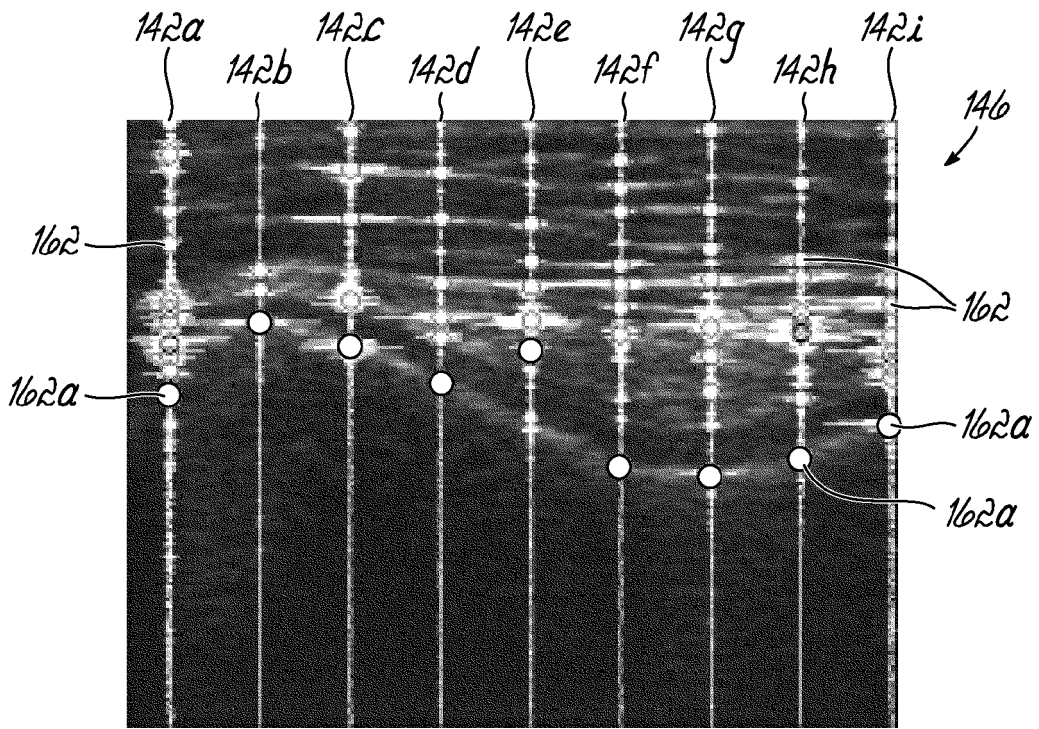


FIG. 10B

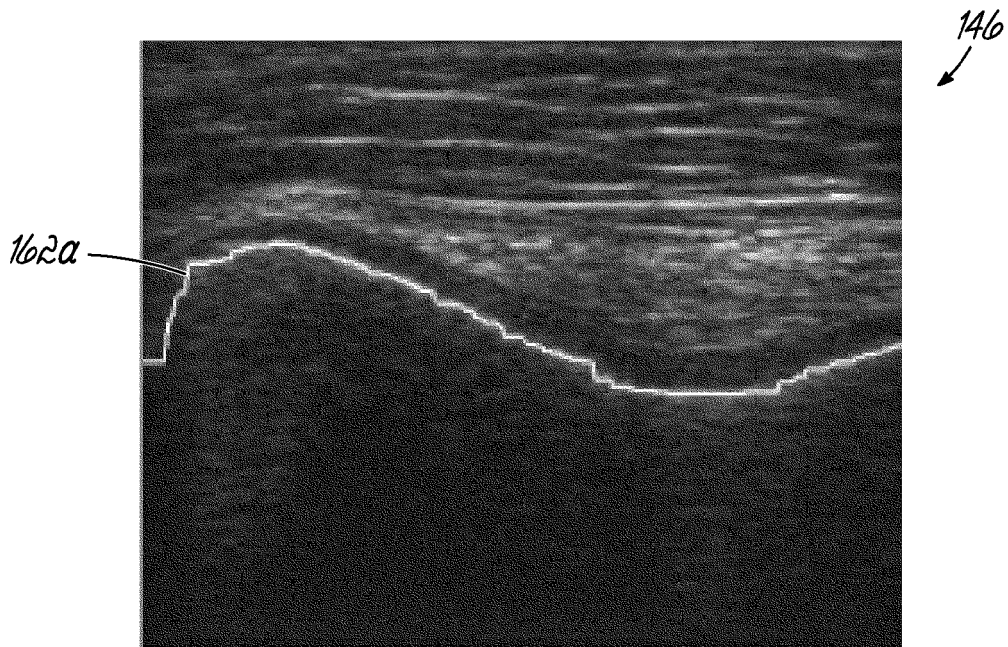


FIG. 10C

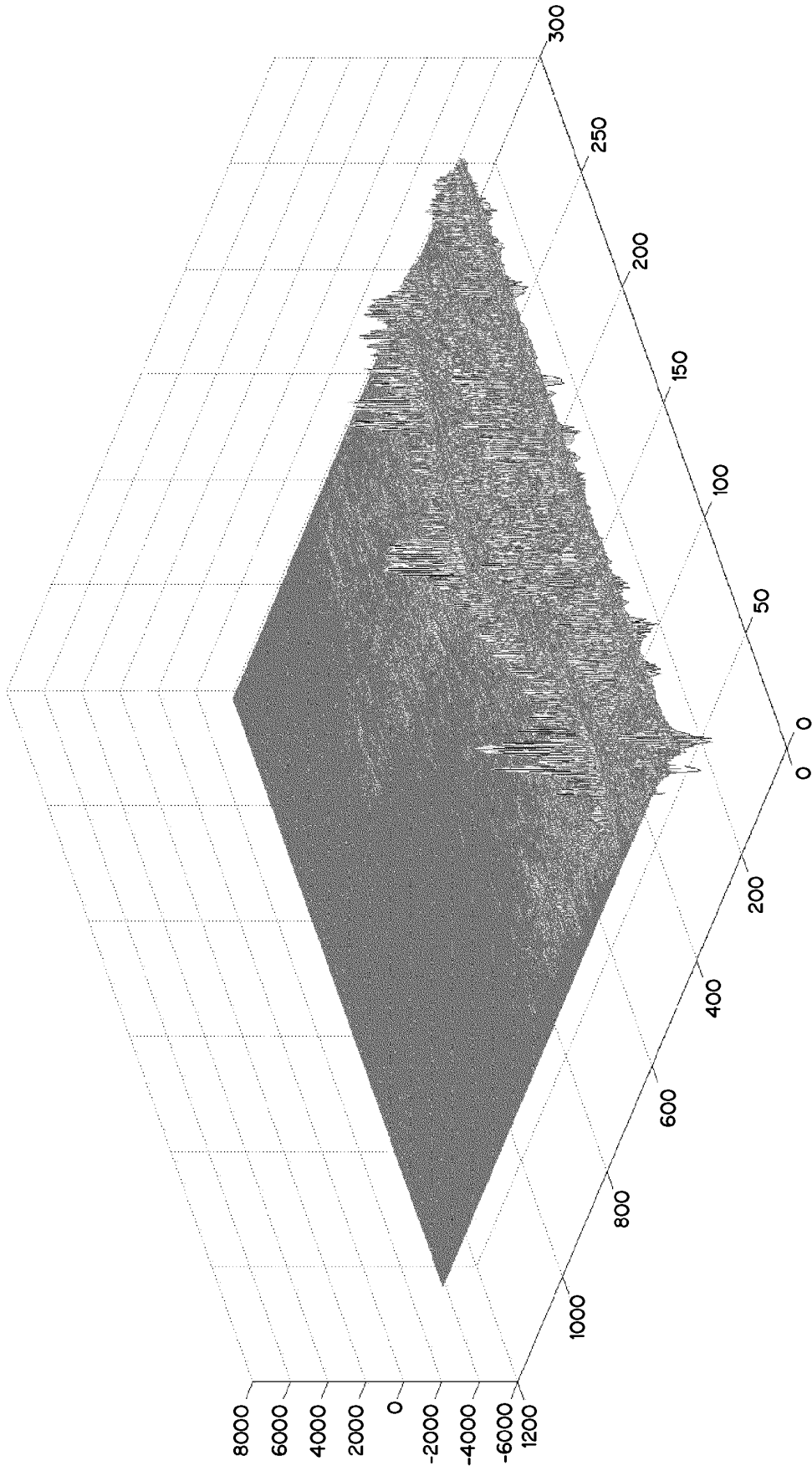


FIG. 10D

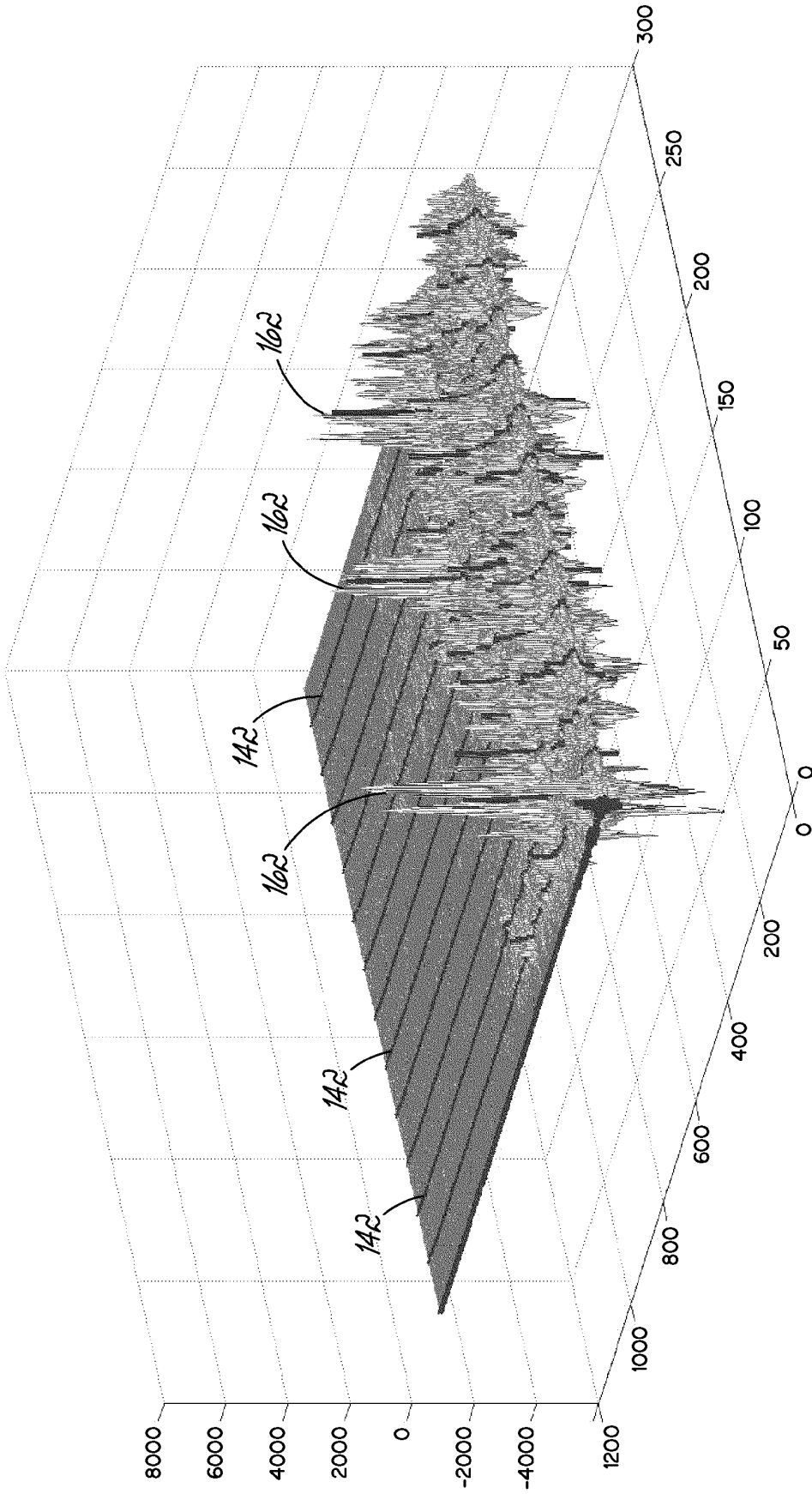
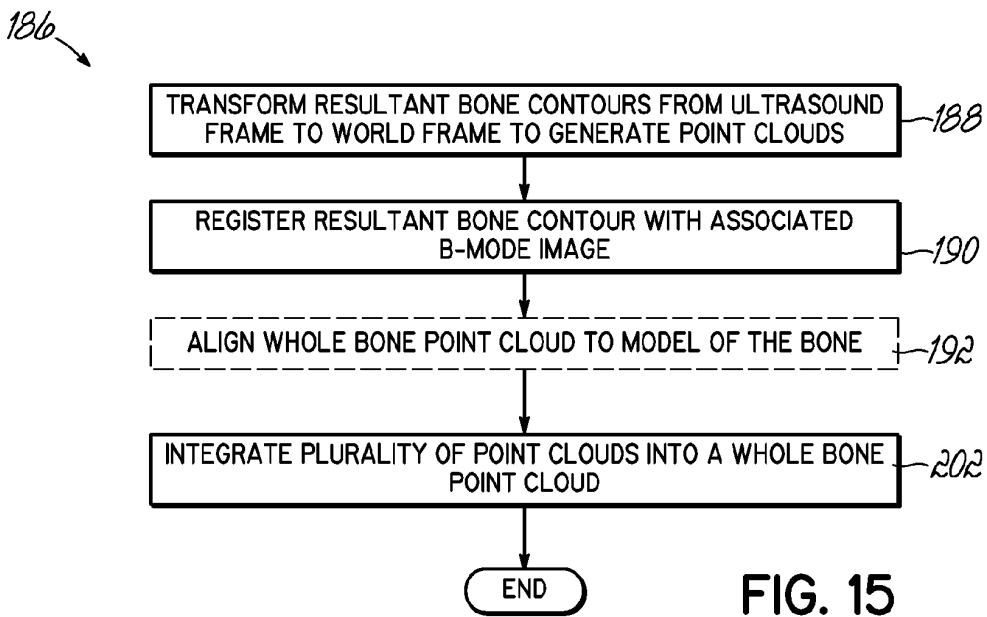
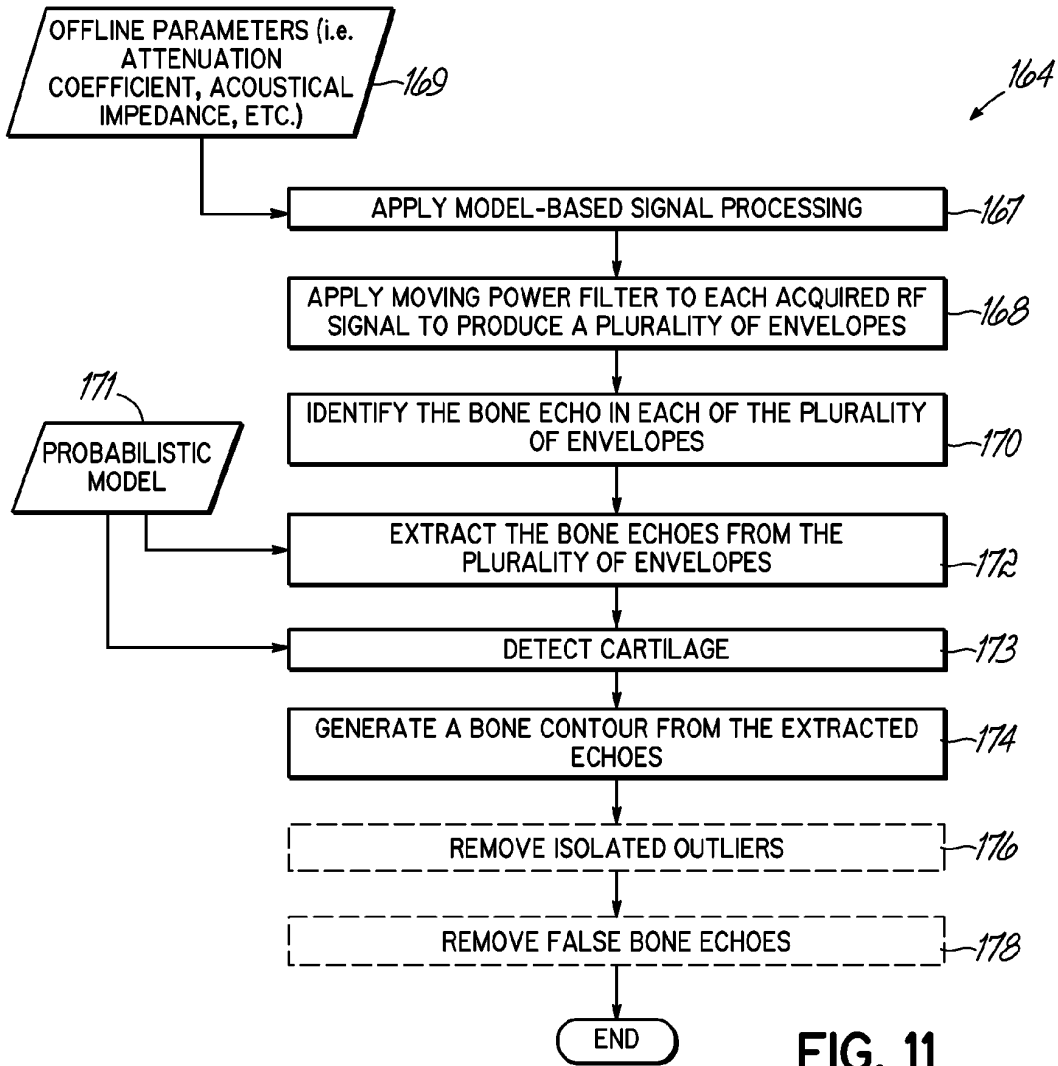


FIG. 10E



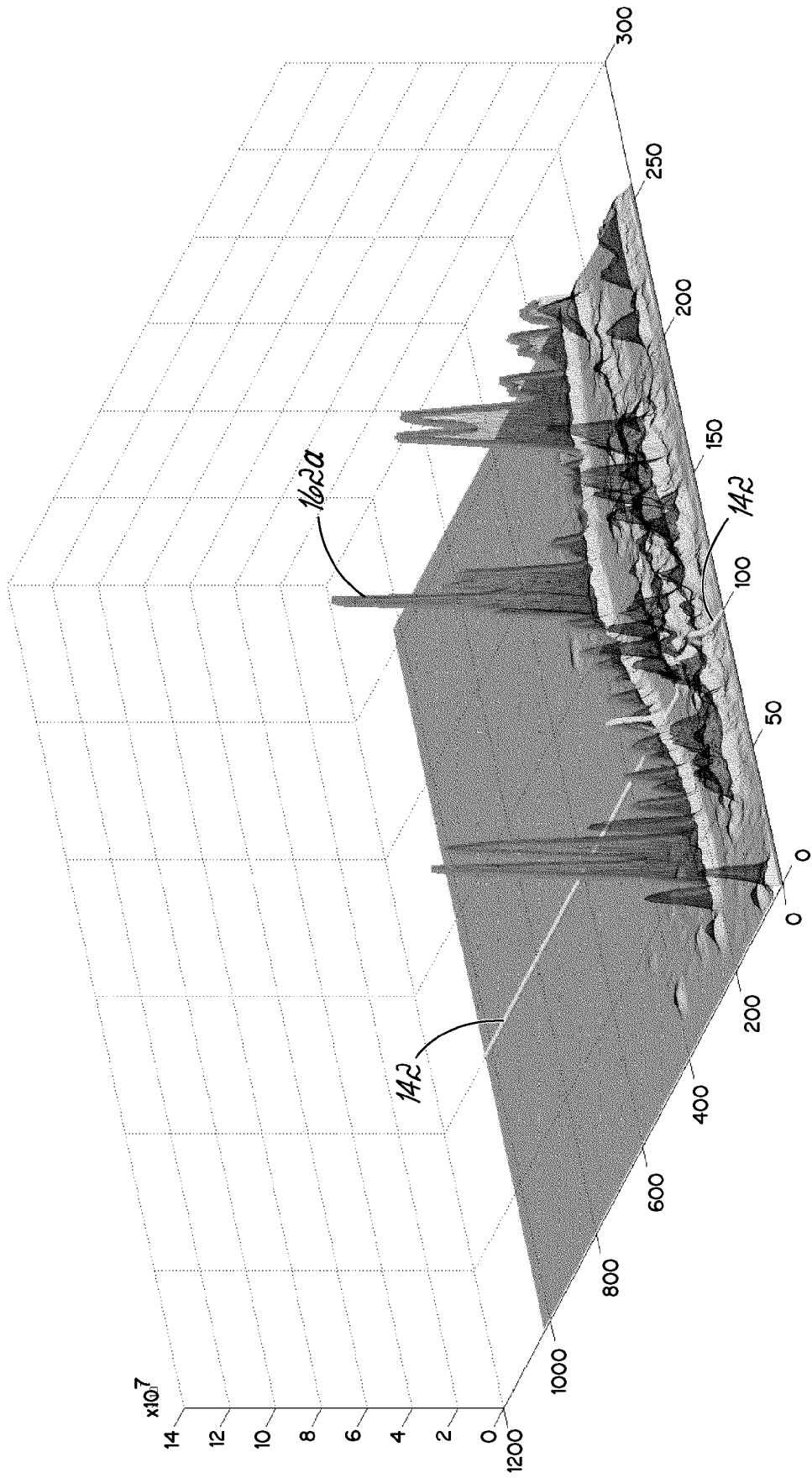


FIG. 12A

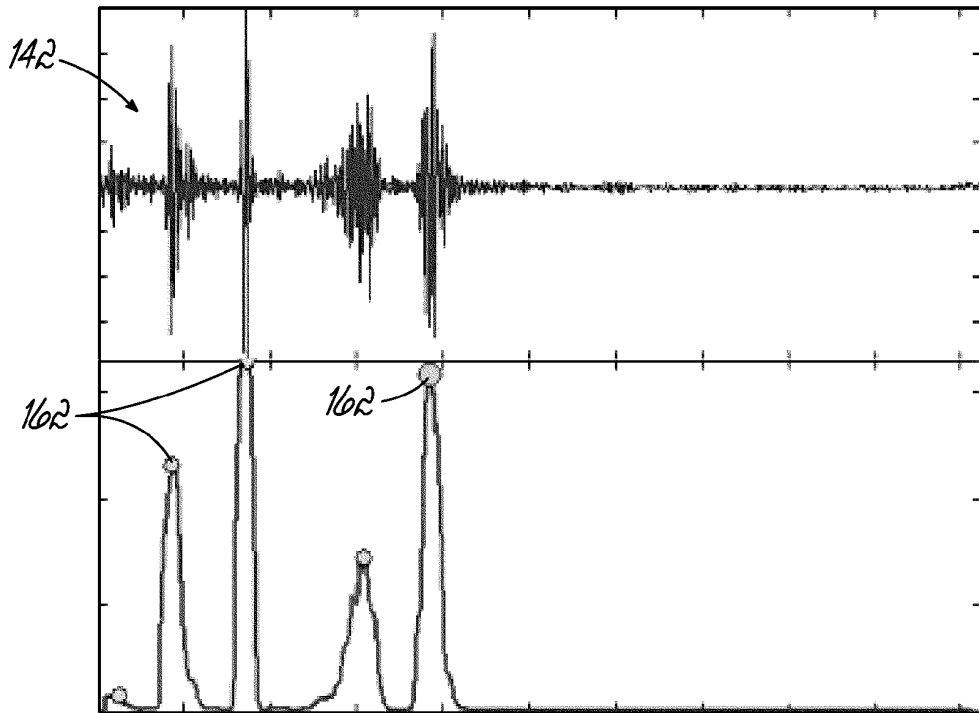


FIG. 12B

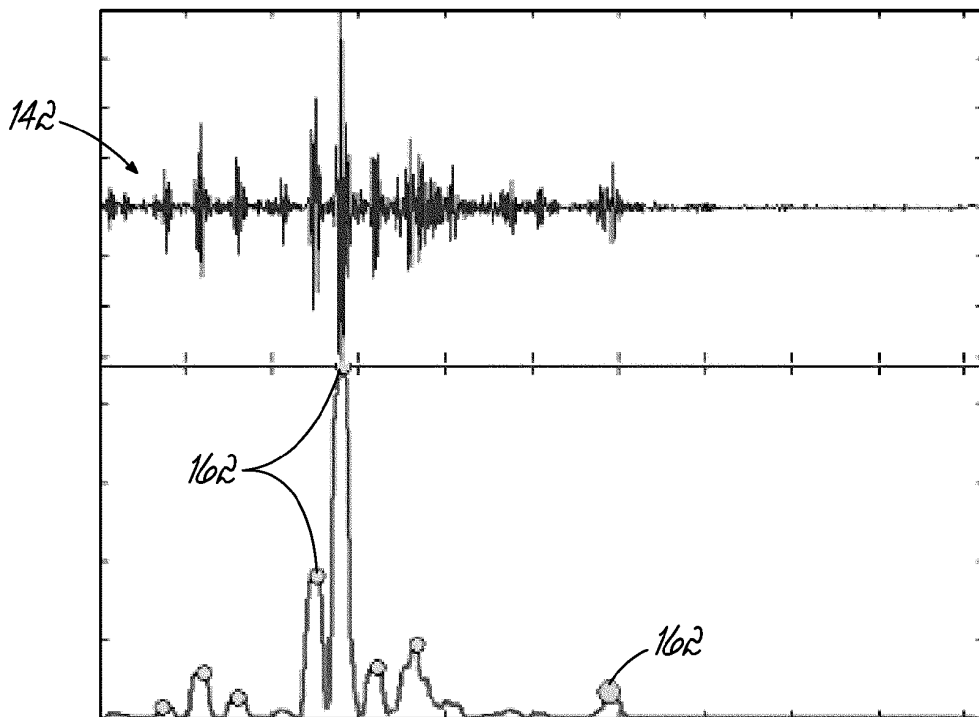


FIG. 12C

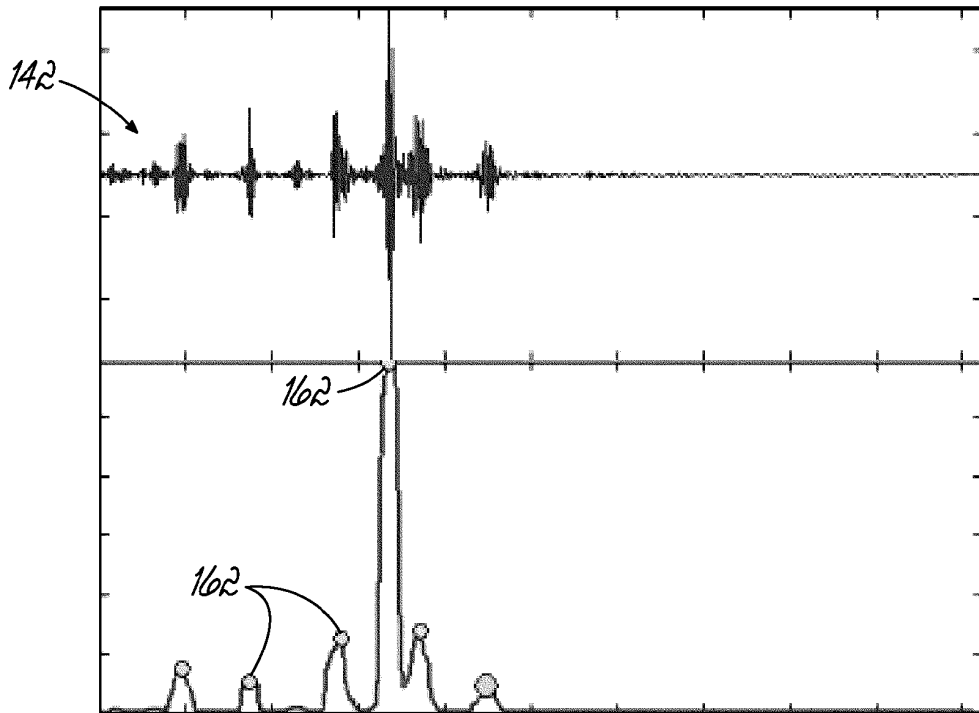


FIG. 12D

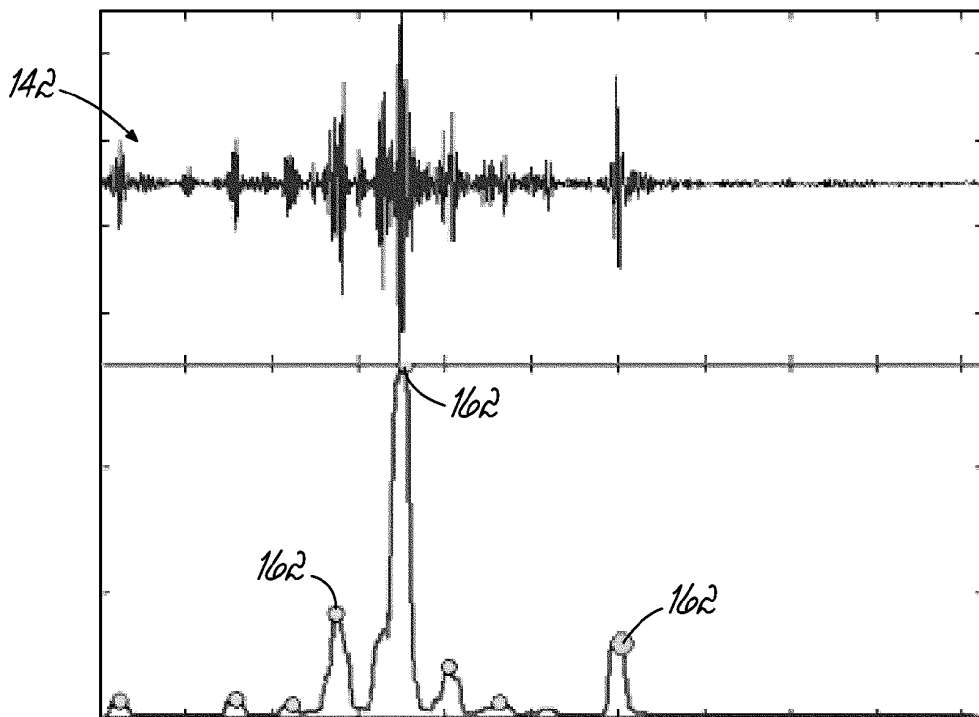


FIG. 12E

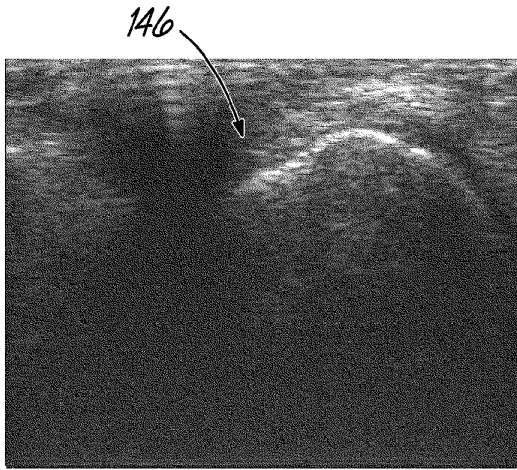


FIG. 13A

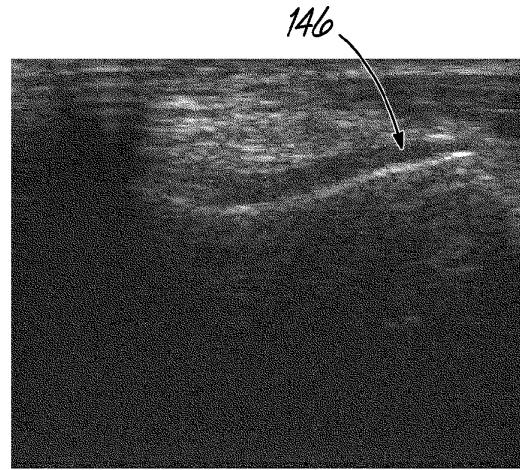


FIG. 13D

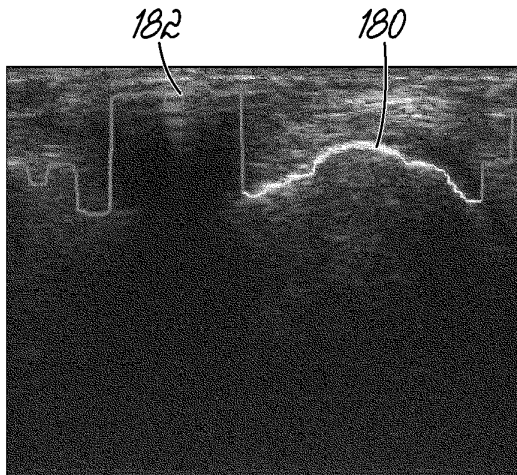


FIG. 13B

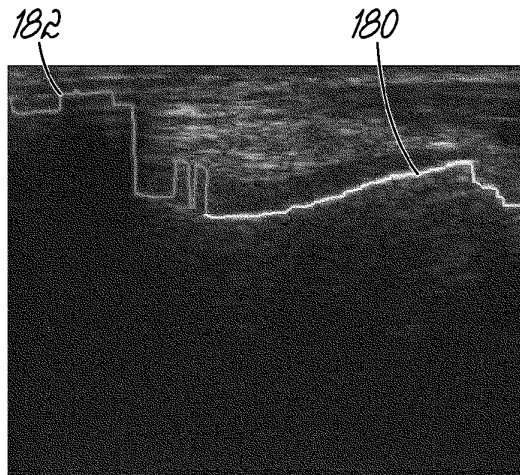


FIG. 13E

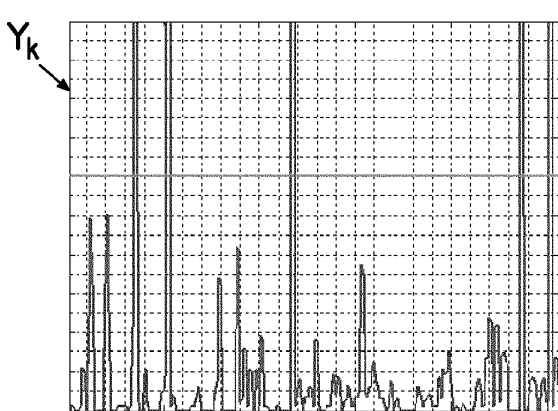


FIG. 13C

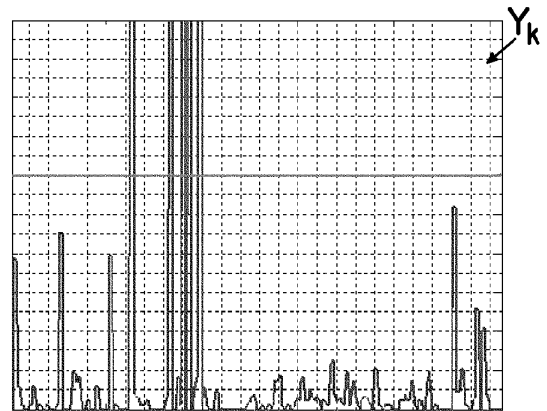


FIG. 13F

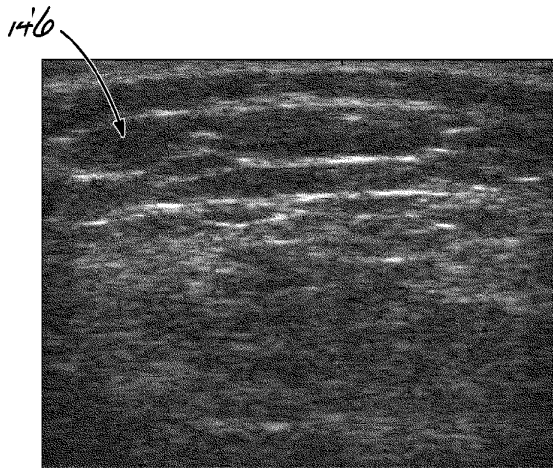


FIG. 14A

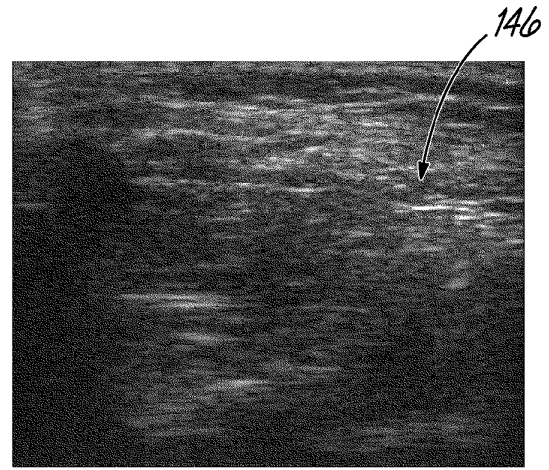


FIG. 14D

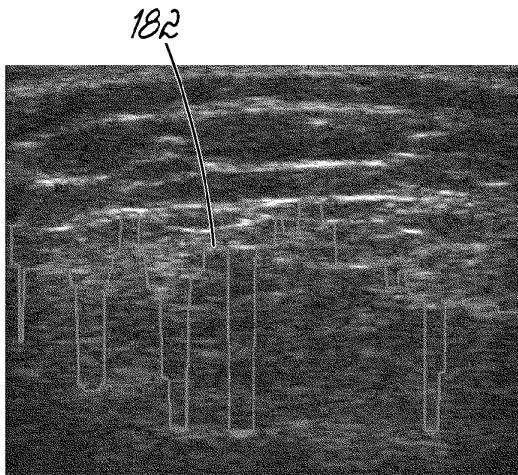


FIG. 14B

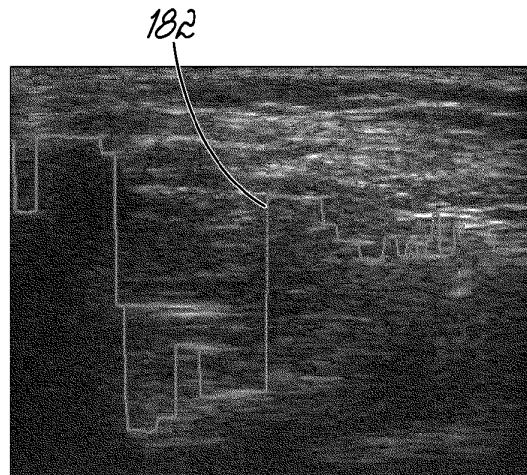


FIG. 14E

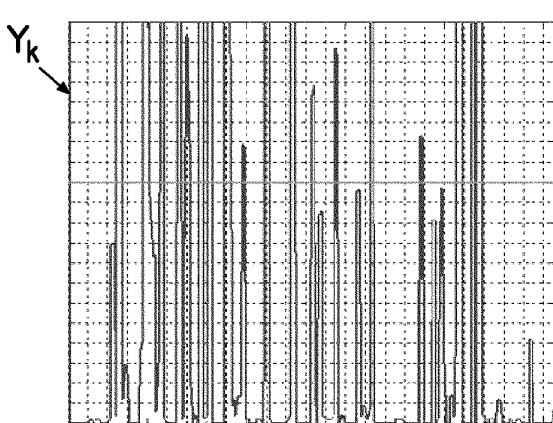


FIG. 14C

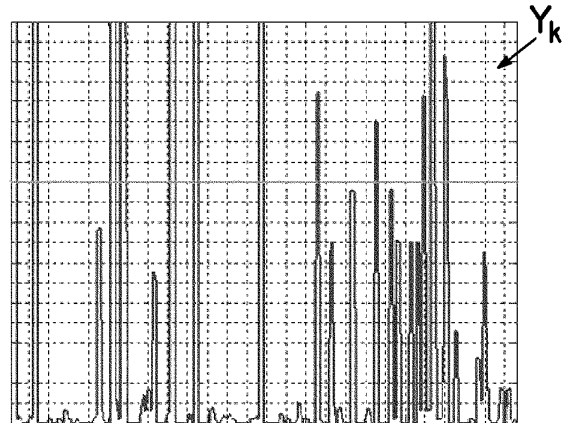


FIG. 14F

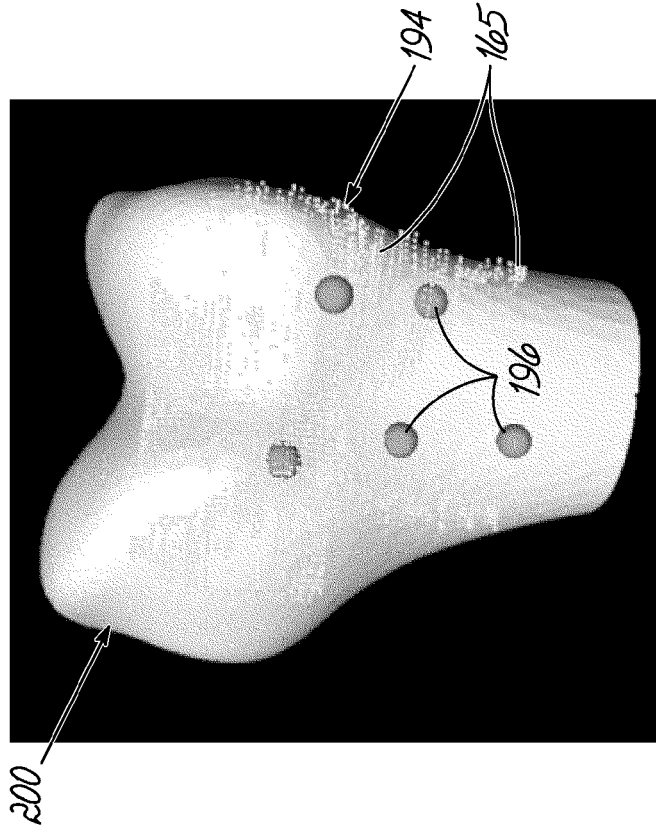


FIG. 16B

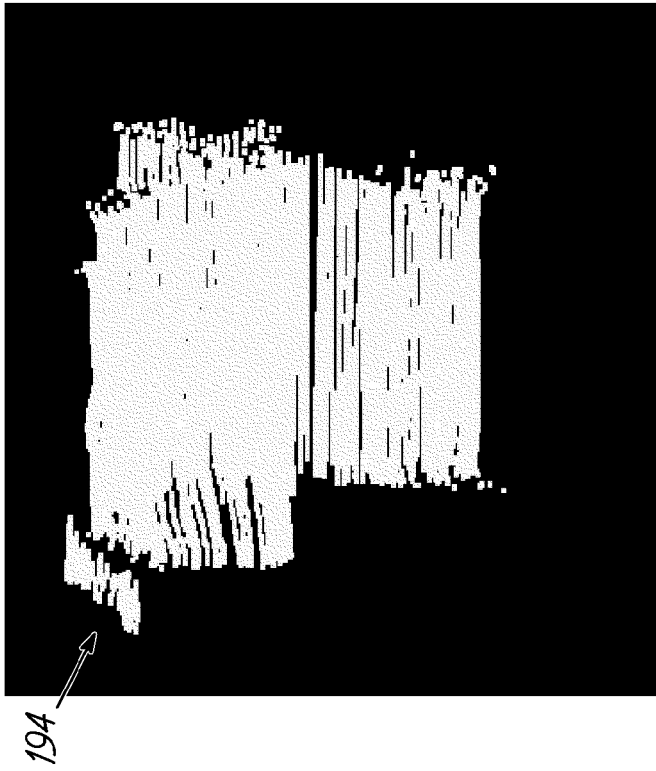


FIG. 16A

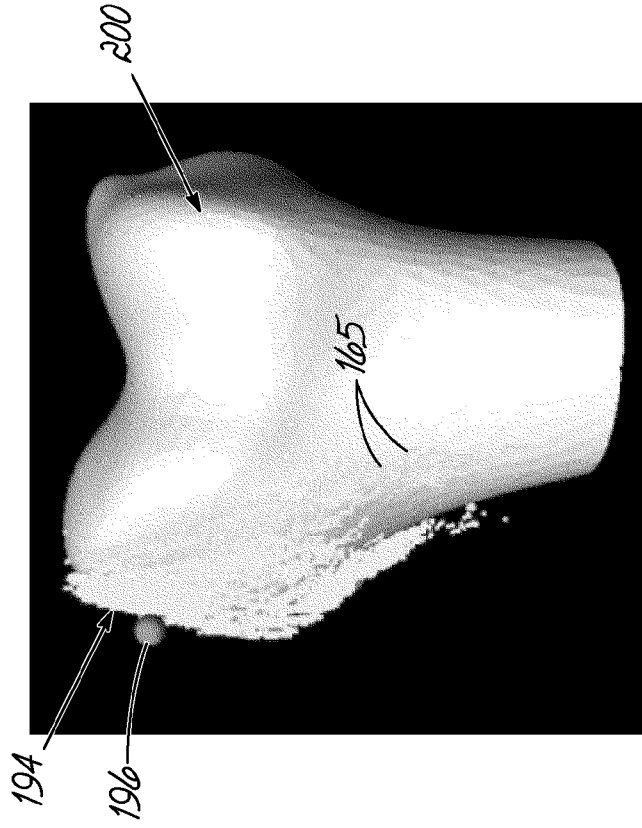


FIG. 16D

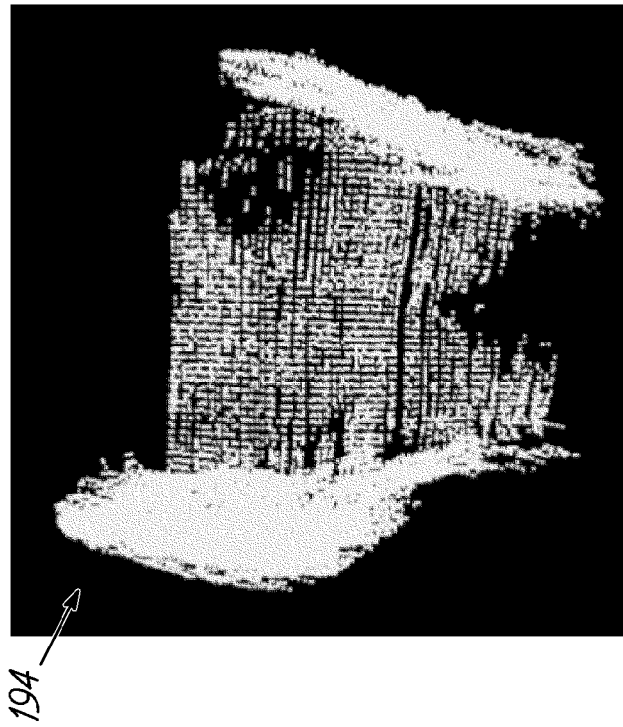


FIG. 16C

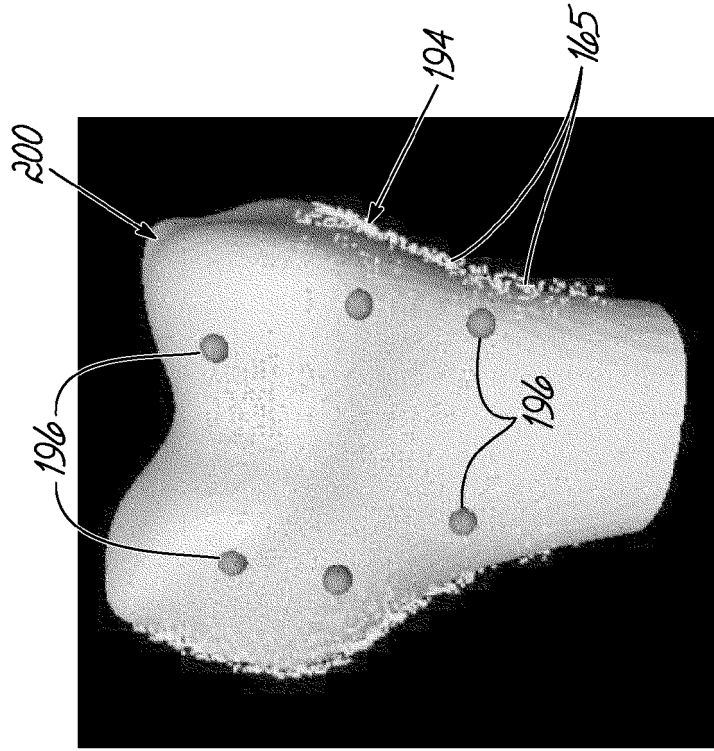


FIG. 17B

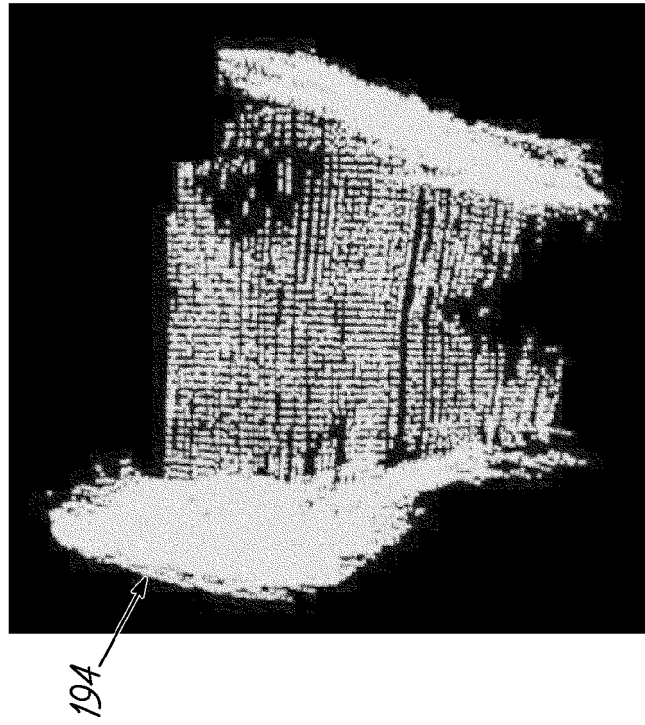


FIG. 17A

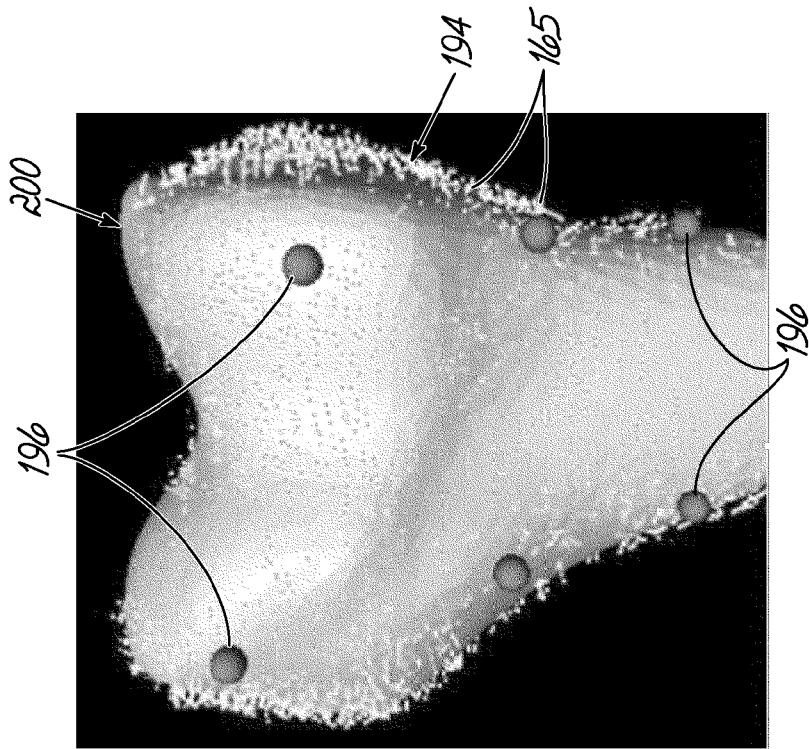


FIG. 17D

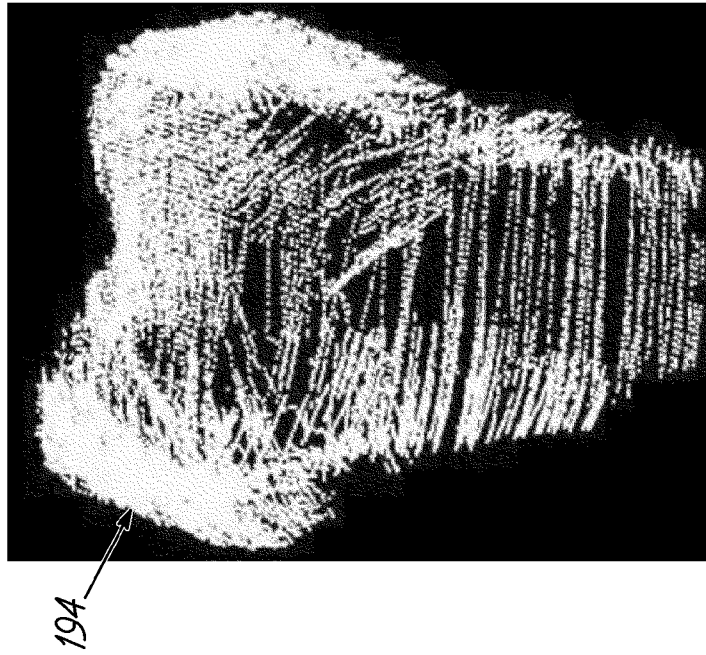


FIG. 17C

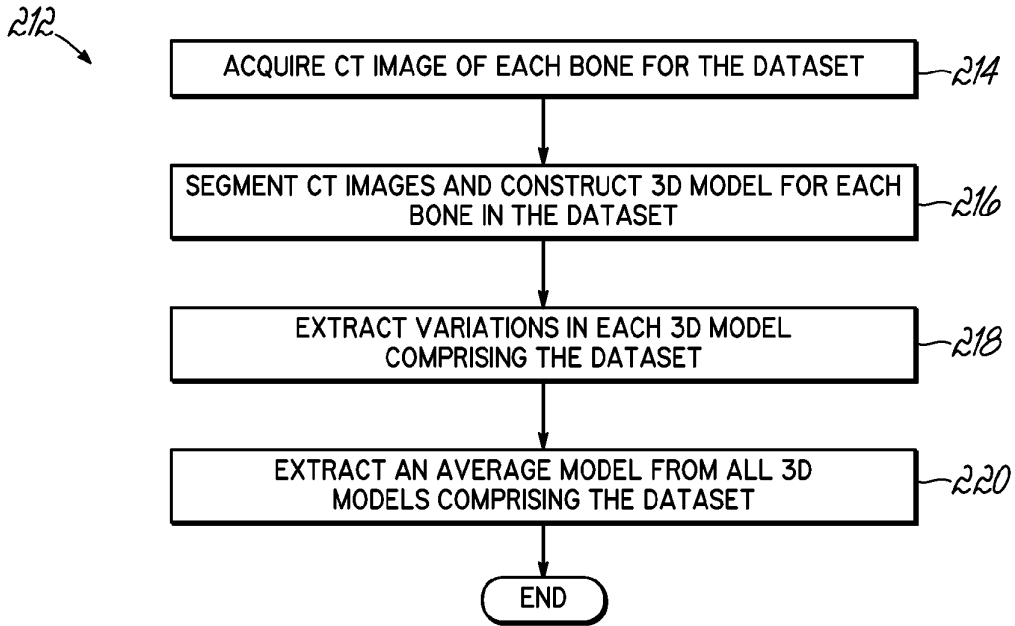


FIG. 18

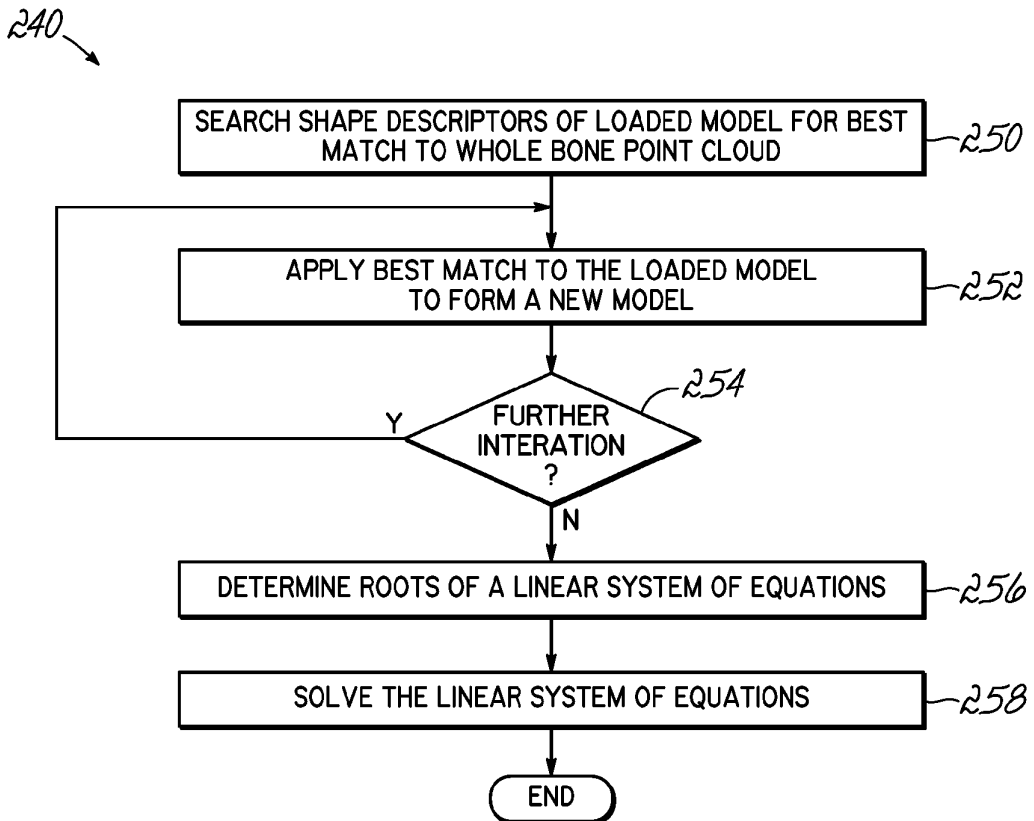


FIG. 19

REFERENCES CITED IN THE DESCRIPTION

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专利名称(译)	超声关节三维重建的方法和装置		
公开(公告)号	EP3213682B1	公开(公告)日	2020-03-04
申请号	EP2017163447	申请日	2011-08-02
[标]申请(专利权)人(译)	JOINTVUE		
申请(专利权)人(译)	JOINTVUE , LLC		
当前申请(专利权)人(译)	JOINTVUE , LLC		
[标]发明人	MAHFOUZ MOHAMED R		
发明人	MAHFOUZ, MOHAMED, R.		
IPC分类号	A61B5/103 A61B8/14 A61B8/00 G06T17/00 A61B34/10 A61B90/00 A61B34/20 G06T7/12 G06T7/149 G06T7/174 A61B8/08		
CPC分类号	A61B8/0875 A61B8/14 A61B8/4245 A61B8/4263 A61B8/483 A61B8/5238 A61B90/37 A61B2034/105 A61B2034/2055 A61B2090/367 A61B2090/378 G06T7/12 G06T7/149 G06T7/174 G06T17/00 G06T2207/10132 G06T2207/30008 G06T2210/41 G06T2210/56		
代理机构(译)	HGF LIMITED		
优先权	61/369848 2010-08-02 US 61/470952 2011-04-01 US PCT/US2011/046318 2011-08-02 WO		
其他公开文献	EP3213682A1		
外部链接	Espacenet		

摘要(译)

一种生成3-D患者特定的肌肉骨骼模型的方法，该方法包括：使用包括换能器阵列（10）的超声探头（60）在多个位置上采集多个射频（“RF”）信号（142）。68）；跟踪3D空间中多个RF信号（142）的获取并生成跟踪数据；在多个RF信号（142）中识别多个骨回波（162a）；从多个骨回波（162a）确定2-D骨轮廓（180）；使用跟踪数据将2-D骨轮廓线（180）转换成3-D点云（194）；并通过将3-D骨骼模型变形为与3-D点云一致（194）来创建3-D患者特定的肌肉骨骼模型（260），其中，变形3-D骨骼模型包括使用优化算法来更改使3-D模型变形的形状描述符。

