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KATSUYAMA(10) **Pub. No.: US 2009/0099455 A1**(43) **Pub. Date: Apr. 16, 2009**(54) **ULTRASOUND DIAGNOSIS METHOD AND APPARATUS****Publication Classification**(51) **Int. Cl.**
A61B 8/14 (2006.01)(52) **U.S. Cl.** **600/459**(57) **ABSTRACT**(76) **Inventor:** **Kimito KATSUYAMA,**
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FALLS CHURCH, VA 22040-0747 (US)(21) **Appl. No.:** **12/248,394**(22) **Filed:** **Oct. 9, 2008**(30) **Foreign Application Priority Data**

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An ultrasound diagnosis apparatus includes an ultrasound probe having a plurality of elements arranged therein, the ultrasound probe transmitting ultrasound toward a subject, receiving an ultrasound signal reflected off the subject, and outputting a received signal; a device that changes a preset assumed sound speed with respect to an actual sound speed of the ultrasound transmitted toward the subject; and a frame position calculation device that determines similarity of each portion between each frame by using speckles in RF data or amplitude images based on two or more of the different assumed sound speeds and calculates frame positions, thereby determining similarity in a stable, uniform, accurate manner without lowering a frame rate.

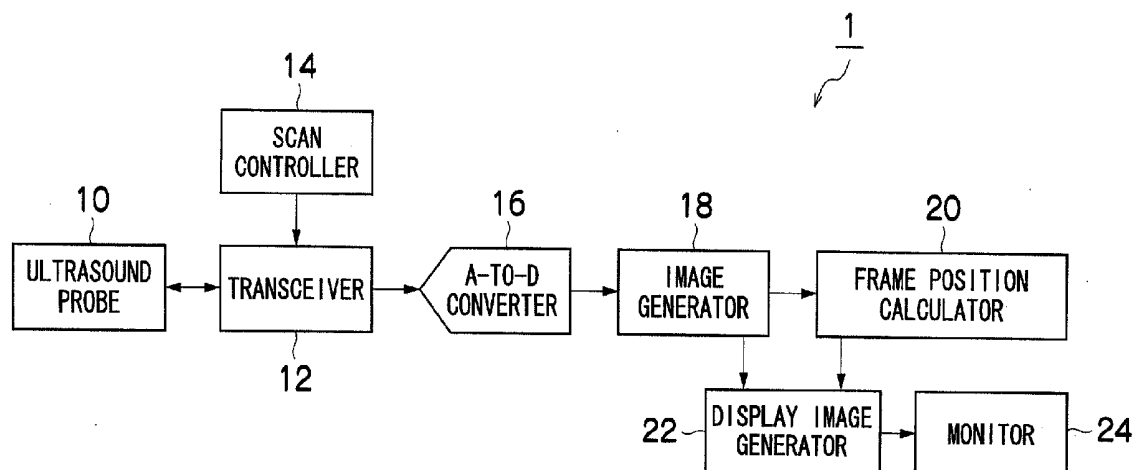


FIG. 1

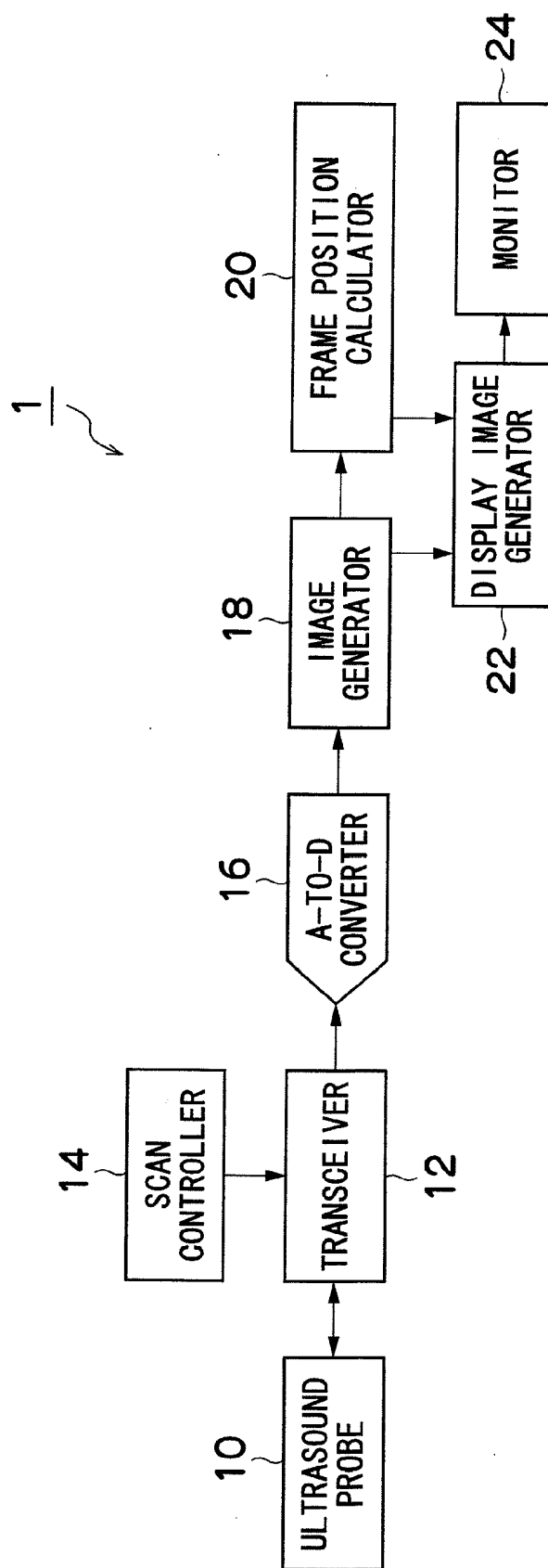


FIG.2

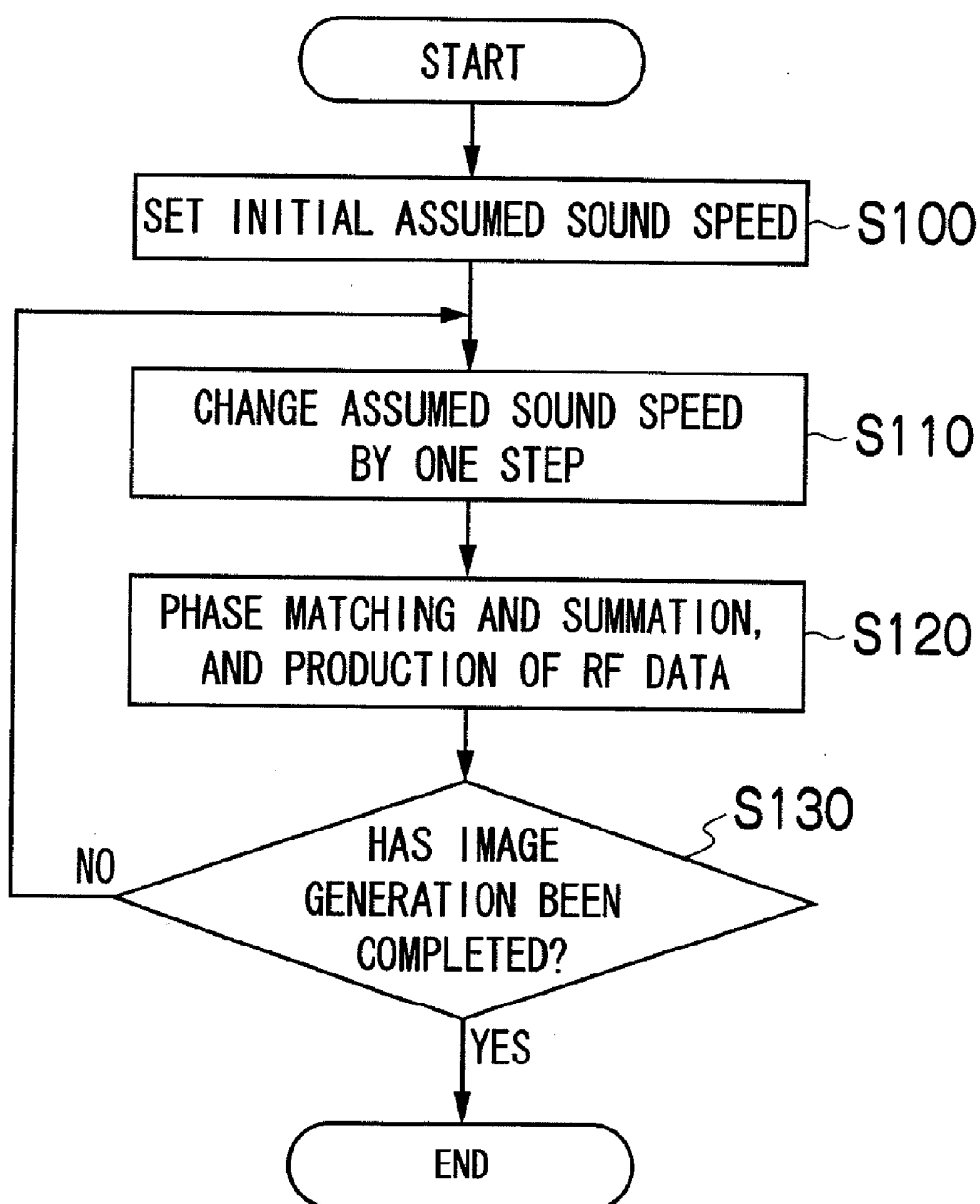


FIG.3

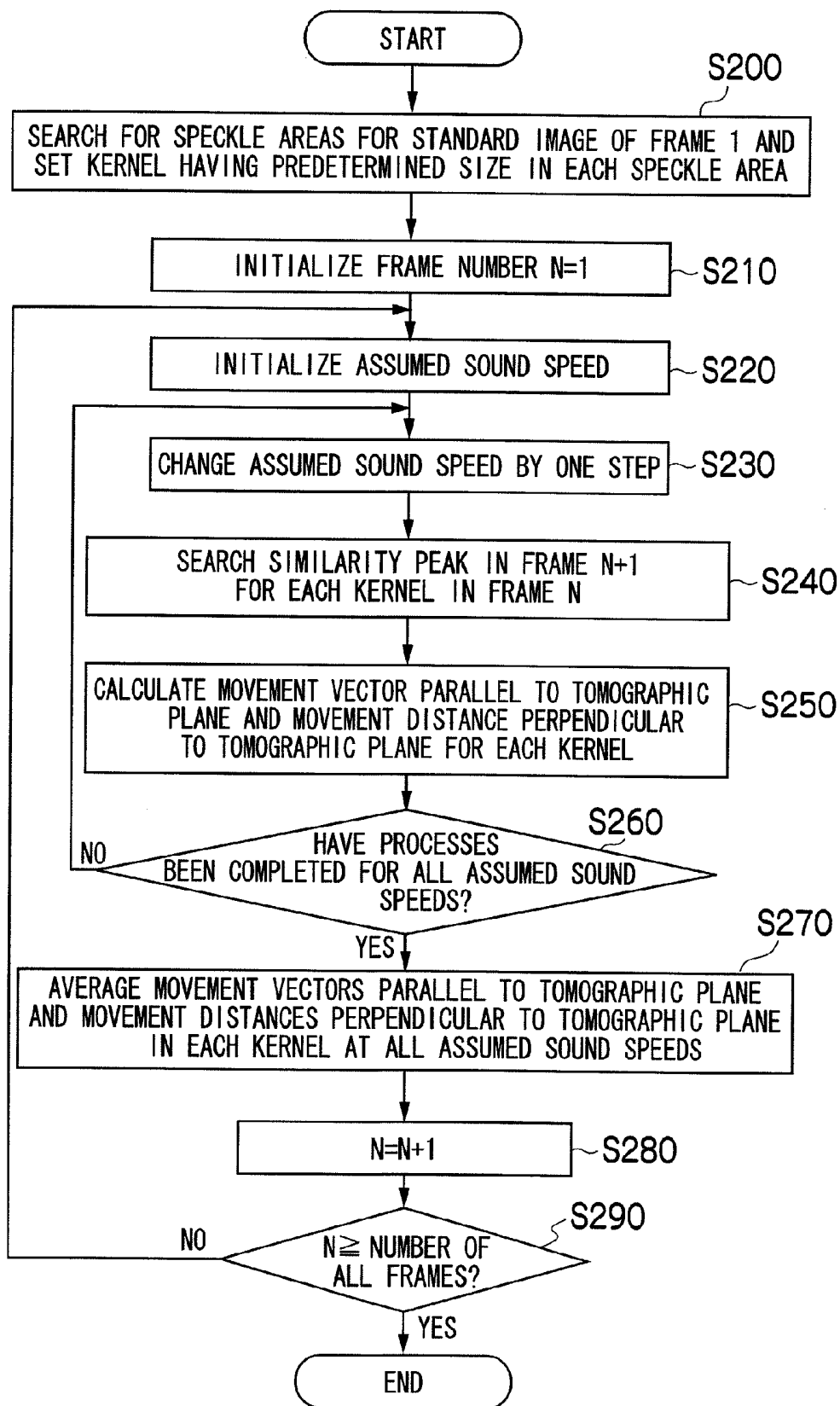


FIG.4

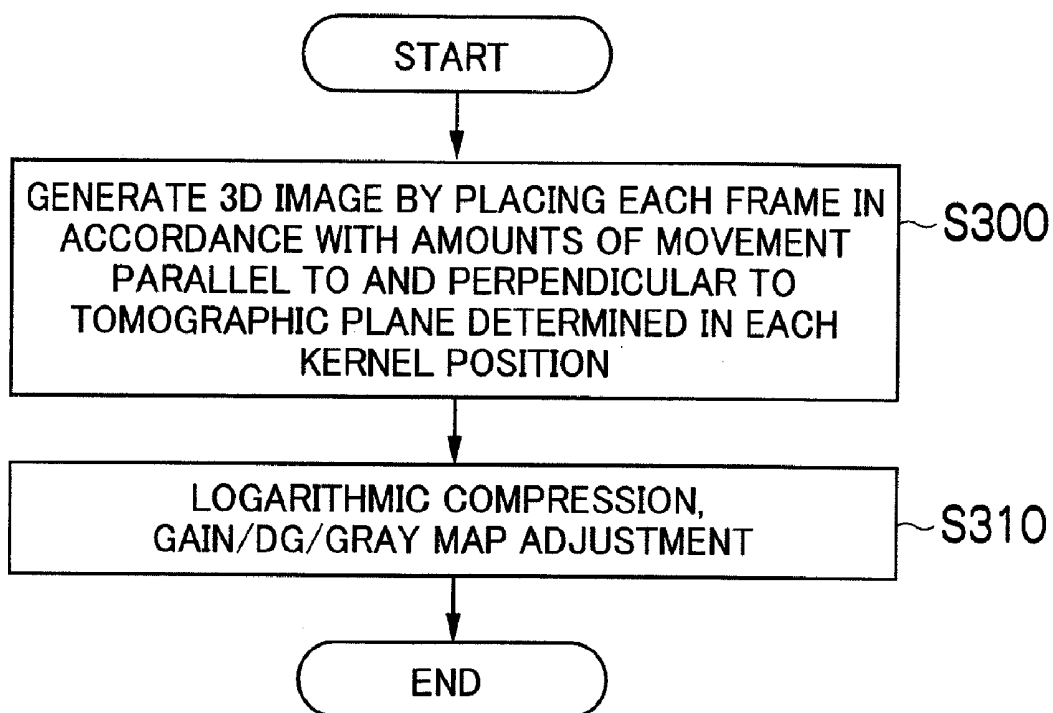


FIG.5

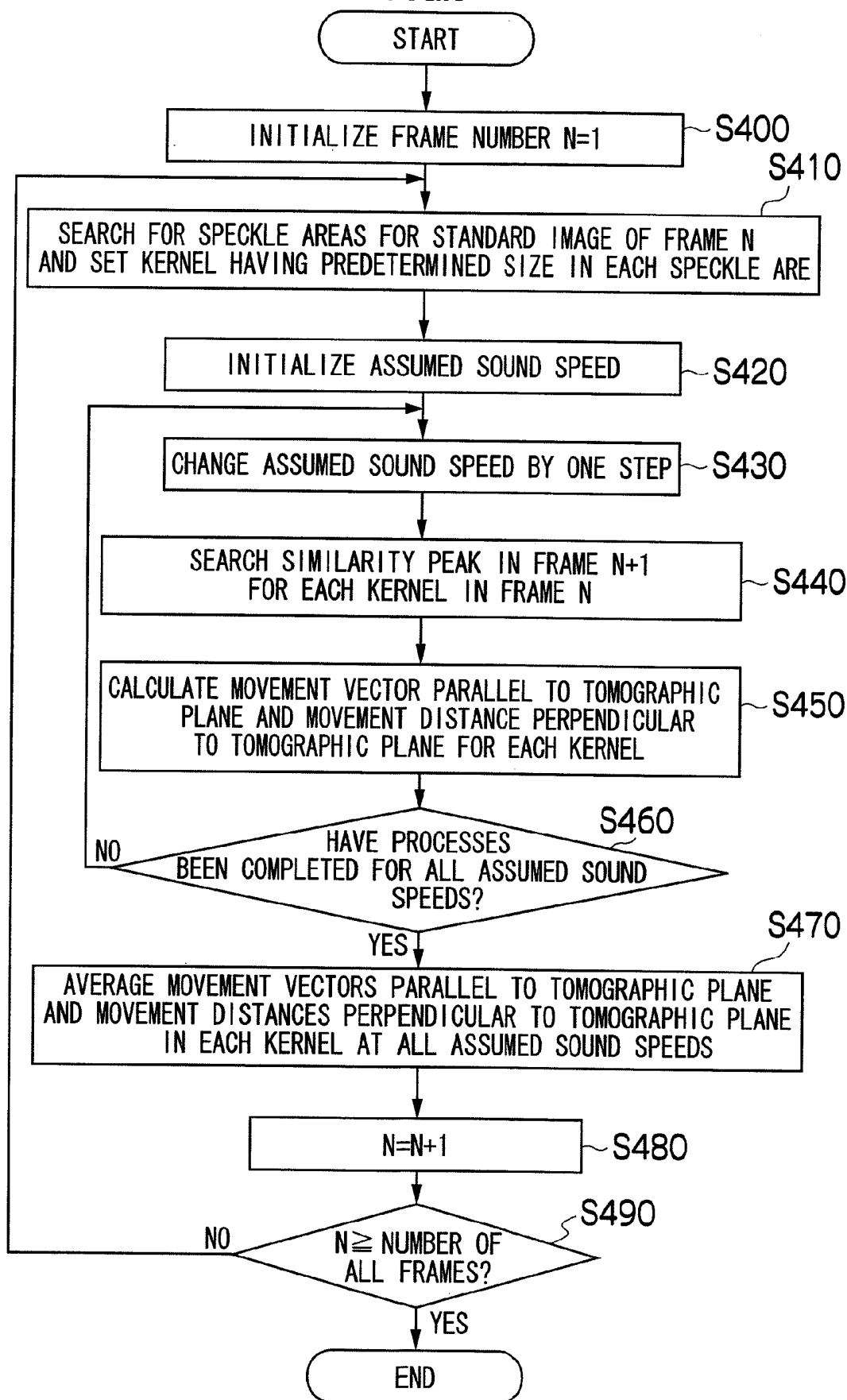
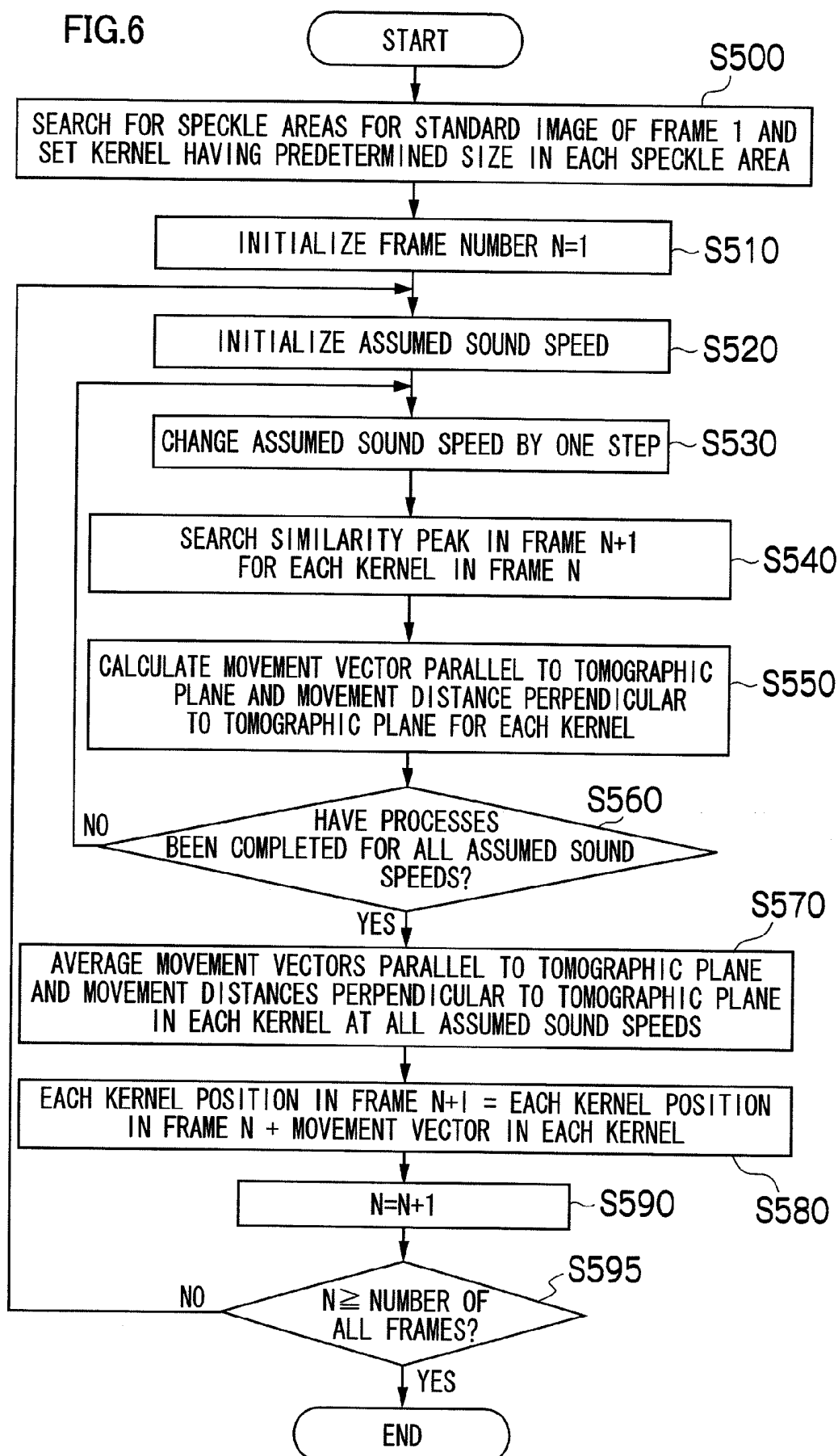


FIG. 6



ULTRASOUND DIAGNOSIS METHOD AND APPARATUS

BACKGROUND OF THE INVENTION

[0001] 1. Field of the Invention

[0002] The present invention relates to an ultrasound diagnosis method and apparatus, and particularly to an ultrasound diagnosis method and apparatus by which inter-frame, inter-portion similarity is determined in a stable, uniform manner.

[0003] 2. Description of the Related Art

[0004] Conventionally, ultrasound is used to acquire tomographic images of a subject for medical diagnosis. For example, when the motion of the heart or other organs is measured, "similarity" is used between frames to determine which portion in a frame corresponds to a certain portion in a previous frame and align these portions. As a conventional method for determining inter-frame, inter-portion similarity, a cross-correlation method, a normalized cross-correlation method, an SAD (source to axis distance) method, an SSD (source to surface distance) method, and other technologies are known. These technologies are used in a large number of fields, such as panoramic image synthesis, 3D image synthesis, motion/rotation correction, and speckle and tissue tracking.

[0005] For example, a technology is known in which one focuses on inter-frame change in texture to track probing positions without using a sensor (see Japanese Patent Application Laid-Open No. 2002-102223, for example). This technology is based on the fact that change in a speckle pattern that appears in ultrasound tomographic images with respect to shift in probing position is independent of the state of tissue being observed, and the change in a speckle pattern is used to identify the three-dimensional position of an ultrasound tomographic image.

[0006] That is, in this technology, a peak value of a correlation function for images before and after movement of an ultrasound probe is used to measure a movement vector in a tomographic image plane. A plurality of small areas are cut from one of the images before and after the movement. The peak position and the peak value of the correlation function for the areas and the other one of the images are used to measure the angle of rotation.

SUMMARY OF THE INVENTION

[0007] The conventional technology described above that uses inter-frame similarity in texture can work in a more stable manner when the number of types of typically used texture is greater and work more accurately when the resolution of texture is higher. However, on the other hand, higher resolution of texture leads to greater inter-frame change, which disadvantageously reduces accuracy greatly.

[0008] Although the number of types of texture in a certain portion in an image can be increased by using a plurality of sets of RF data or amplitude images obtained by sending and receiving beams having different frequencies, extra transmission operations are disadvantageously necessary. Further, since a signal is divided, and the positional relationship between the probe and the reflector between transmission and reception operations is changed, the frame rate and resolution are lowered, and hence the accuracy is degraded.

[0009] The resolution of texture becomes lower when the discrepancy between the assumed sound speed and the actual sound speed during image generation is greater. Since the amount of discrepancy between the assumed sound speed and the actual sound speed varies from location to location, the resolution of texture or speckle varies from portion to portion,

disadvantageously resulting in reduced accuracy in similarity and reduced uniformity, that is, accuracy varying from portion to portion.

[0010] Further, in a freehand-based 3D image reconstruction in the related art described above, a similarity value is used to estimate the distance over which the probe has moved. However, since the relationship between the similarity value and the distance over which the probe has moved varies with the resolution of speckle, accuracy in estimation disadvantageously decreases.

[0011] The present invention has been made in view of the above circumstances, and an object of the present invention is to provide an ultrasound diagnosis method and apparatus by which similarity can be determined in a stable, uniform, accurate manner without lowering the frame rate.

[0012] To achieve the above object, a first aspect of the present invention provides an ultrasound diagnosis apparatus including an ultrasound probe having a plurality of elements arranged therein, the ultrasound probe transmitting ultrasound toward a subject, receiving an ultrasound signal reflected off the subject, and outputting a received signal; a device that changes a preset assumed sound speed with respect to an actual sound speed of the ultrasound transmitted toward the subject; and a frame position calculation device that determines similarity of each portion between each frame by using speckles in RF data or amplitude images based on two or more of the different assumed sound speeds and calculates frame positions.

[0013] Therefore, since a plurality of different speckle patterns based on assumed sound speeds are used, similarity can be determined in a stable manner. Further, since a variety of patterns from a low-resolution pattern to a high-resolution pattern are uniformly contained, similarity can be determined in a stable, accurate manner. Moreover, although an optimal sound speed (actual sound speed) is different from each portion, speckles with lower resolution to speckles with higher resolution are similarly contained, similarity can be uniformly determined in any portion.

[0014] According to a second aspect of the present invention, in the ultrasound diagnosis apparatus according to the first aspect, the RF data or amplitude images are generated from received data produced by changing the assumed sound speed by multiple steps in a single transmission operation.

[0015] Therefore, since similarity is produced from received data obtained from the same transmission, the frame rate will not be lowered, and reduction in accuracy due to shift between transmission operations will not occur.

[0016] According to a third aspect of the present invention, in the ultrasound diagnosis apparatus according to the first or the second aspect, the RF data or amplitude images are generated from data whose resolution in a direction in which the elements are arranged is higher than or equal to a distance between the elements.

[0017] Similarity can thus be accurately determined.

[0018] Similarly, to achieve the above object, a fourth aspect of the present invention provides an ultrasound diagnosis method including: transmitting ultrasound from an ultrasound probe having a plurality of elements arranged therein toward a subject and receiving an ultrasound signal reflected off the subject; changing a preset assumed sound speed with respect to an actual sound speed of the ultrasound transmitted toward the subject; and determining similarity of each portion between each frame by using speckles in RF data or amplitude images based on two or more of the different assumed sound speeds and calculating frame positions.

[0019] Therefore, since a plurality of different speckle patterns based on assumed sound speeds are used, similarity can

be determined in a stable manner. Further, since a variety of patterns from a low-resolution pattern to a high-resolution pattern are uniformly contained, similarity can be determined in a stable, accurate manner. Moreover, although an optimal sound speed (actual sound speed) is different from each portion, speckles with lower resolution to speckles with higher resolution are similarly contained, similarity can be uniformly determined in any portion.

[0020] According to a fifth aspect of the present invention, in the ultrasound diagnosis method according to the fourth aspect, the RF data or amplitude images are generated from received data produced by changing the assumed sound speed by multiple steps in a single transmission operation.

[0021] Therefore, since similarity is produced from received data obtained from the same transmission, the frame rate will not be lowered, and reduction in accuracy due to shift between transmission operations will not occur.

[0022] According to a sixth aspect of the present invention, in the ultrasound diagnosis method according to the fourth or the fifth aspect, the RF data or amplitude images are generated from data whose resolution in a direction in which the elements are arranged is higher than or equal to a distance between the elements.

[0023] Similarity can thus be accurately determined.

[0024] As described above, according to any of the aspects of the present invention, since a plurality of different speckle patterns based on assumed sound speeds are used, similarity can be determined in a stable manner. Further, since a variety of patterns from a low-resolution pattern to a high-resolution pattern are uniformly contained, similarity can be determined in a stable, accurate manner. Moreover, although an optimal sound speed (actual sound speed) is different from each portion, speckles with lower resolution to speckles with higher resolution are similarly contained, similarity can be uniformly determined in any portion.

BRIEF DESCRIPTION OF THE DRAWINGS

[0025] FIG. 1 is a system configuration diagram showing a schematic configuration of an embodiment of an ultrasound diagnosis apparatus according to the present invention;

[0026] FIG. 2 is a flowchart showing the operation of an image generator;

[0027] FIG. 3 is a flowchart showing the flow of processes performed in a frame position calculator;

[0028] FIG. 4 is a flowchart showing the contents of processes performed in a display image generator;

[0029] FIG. 5 is a flowchart showing a first variation of processes performed in the frame position calculator; and

[0030] FIG. 6 is a flowchart showing a second variation of processes performed in the frame position calculator.

DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENTS

[0031] An ultrasound diagnosis method and apparatus according to the present invention will be described below in detail with reference to the accompanying drawings.

[0032] The present invention aims to use speckles in RF data or amplitude images generated at different assumed sound speeds to determine similarity in a stable, uniform, accurate manner without lowering the frame rate, and calculate frame positions.

[0033] With respect to the actual ultrasound speed (actual sound speed) transmitted toward a subject, ultrasound speeds

set by changing an initial ultrasound speed stepwise by a predetermined amount multiple times are called set sound speeds or assumed sound speeds. The actual sound speed is also referred to as an optimal sound speed.

[0034] The present invention has been made in view of the following points: That is, (1) Since speckle patterns produced at different assumed sound speeds are different from one another, similarity is determined in a more stable manner by using the different assumed sound speeds. (2) Since speckle patterns produced at different assumed sound speeds are not only simply different from one another, but also uniformly contain a variety of speckle patterns from low-resolution speckle patterns to high-resolution speckle patterns, similarity is calculated in a more stable, accurate manner. (3) Although the discrepancy between an assumed sound speed and the optimal sound speed varies from location to location, using a plurality of assume sound speeds allows any portion to uniformly contain, in a similar manner to some extent, a variety of patterns from low-resolution patterns to high-resolution patterns. Similarity can therefore be calculated uniformly in any portion with greater accuracy. (4) Since similarity can be produced from received data obtained in the same single transmission, no extra transmission is necessary, and there is no shift between transmission operations.

[0035] A description will be made of freehand-based 3D image generation will be described below by way of example.

[0036] FIG. 1 is a system configuration diagram showing a schematic configuration of an embodiment of an ultrasound diagnosis apparatus according to the present invention.

[0037] As shown in FIG. 1, an ultrasound diagnosis apparatus 1 of the present embodiment uses ultrasound to capture and display ultrasound images of a site to be diagnosed in a subject. The ultrasound diagnosis apparatus 1 includes an ultrasound probe 10, a transceiver 12, a scan controller 14, an A-to-D converter 16, an image generator 18, a frame position calculator 20, a display image generator 22, and a monitor 24.

[0038] The ultrasound probe 10 transmits ultrasound toward a site to be diagnosed in the body of a subject and receives the ultrasound reflected off the body. The ultrasound probe 10 of the present embodiment includes a plurality of ultrasound transducers that form a one-dimensional ultrasound transducer array, and each of the ultrasound transducers is formed of an oscillator, for example, a PZT element or other piezoelectric elements with electrodes formed at both ends thereof. The electrodes are connected to the transceiver 12 via signal lines. When a voltage is applied to the electrodes, the oscillator produces ultrasound. The oscillator, when receiving reflected ultrasound, produces an electric signal and outputs it as a received signal.

[0039] The transceiver 12 sends an ultrasound transmission signal to the ultrasound probe 10 to cause the oscillators to produce ultrasound and transmit it based on a delay received from the scan controller 14. The elements in the ultrasound probe 10 receive reflected ultrasound and output the received signals, and the transceiver 12 then amplifies the received signals as they are (without performing reception focusing).

[0040] The A-to-D converter 16 receives the received ultrasound signals from the transceiver 12, AD-converts them, and sends the resultant signals to the image generator 18. In the image generator 18, the stored data received from the elements undergo reception focusing using delays based on variously set sound speeds (referred to as assumed sound speeds as compared to the actual sound speed transmitted to the

subject, as described above), which will be described later in detail, and RF data based on the assumed sound speeds are produced.

[0041] The frame position calculator 20 uses a plurality of assumed sound speeds to calculate frame positions. The display image generator 22 uses the resultant images generated in the image generator 18 and the resultant frame positions calculated in the frame position calculator 20 to generate a 3D image to be displayed on the monitor 24.

[0042] The operation of the image generator 18 in the configuration of the apparatus shown in FIG. 1 will be described with reference to the flowchart shown in FIG. 2.

[0043] The image generator 18 generates images from data obtained at variously changed assumed sound speeds.

[0044] First, in the step S100 in FIG. 2, an initial assumed sound speed to be variously changed is set. The initial value is not limited to a specific one, but may be determined as appropriate, for example, 1400 [m/s].

[0045] Using the thus set initial value, the transceiver 12, which is under the control of the scan controller 14, transmits a signal to the ultrasound probe 10, which then acquires data based on the initial assumed sound speed and sends the data to the image generator 18.

[0046] In the step S110, the assumed sound speed is changed by one step that corresponds to a predetermined amount, and the changed assumed sound speed is used to acquire ultrasound data. The predetermined amount of one step is not particularly limited to a specific value, but may be, for example, 20 [m/s], 10 [m/s], or 40 [m/s]. The assumed sound speed is then successively changed by the predetermined amount.

[0047] In the step S120, the resultant data based on the assumed sound speeds undergo phase matching and summation. RF (Radio Frequency) data are thus produced. The RF data contain amplitude information and phase information. The RF data is created by thus using images obtained at all the assumed sound speeds.

[0048] In the step S130, a judgment is made as to whether or not the image generation has been completed. When the image generation has not been completed, the control returns to the step S110. In this case, the assumed sound speed is changed by one step, and the image generation continues. The image generation is judged to be completed when the above processes have been completed for all the assumed sound speeds. To this end, for example, the number of assumed sound speed changing steps to complete the image generation may be determined in advance, and a judgment is made as to whether the number is reached.

[0049] The operation of the frame position calculator 20 will be described.

[0050] FIG. 3 is a flowchart showing the flow of processes performed in the frame position calculator 20.

[0051] First, in the step S200, speckle areas are searched for a standard image of the frame 1, and a kernel having a predetermined size is set in each of the detected speckle areas.

[0052] The standard image used to search for speckle areas is an image obtained at an ultrasound speed of 1540 [m/sec].

[0053] A method for judging whether or not searched speckle areas contain speckles is not limited to a specific one, but may be a known method for determining the degree of departure from the Rayleigh distribution. This method is based on the following fact: A speckle pattern that appears in an ultrasound image is a phenomenon in which when a large number of scatterers are distributed at a rate smaller than or equal to the resolution of ultrasound, a large number of processes of superposition of scatterers produce high-intensity and low-intensity portions in an ultrasound signal. When the

scatterers are randomly distributed, the probability density distribution of amplitude values, which are the intensities of ultrasound signals reflected off the scatterers, follows the Rayleigh distribution expressed by $P(x) = (x/s^2) \exp(-x^2/2s^2)$ (where s^2 represents dispersion and normalized as an average of zero). When a certain type of structures increases in tissue, however, the speckle pattern comes to reflect the structures and hence cannot be said to be random. As a result, the probability density function of brightness comes to depart from the Rayleigh distribution. Such a behavior is used to judge whether there are speckles.

[0054] Alternatively, a judgment may be made as to whether there are speckles by using a phase change characteristic in which when assumed sound speed is changed to produce RF data from received ultrasound images, the phase is random in the case of speckle irrespective of the assumed sound speeds.

[0055] Still alternatively, the user may specify speckle areas.

[0056] In the step S210, the frame number n is initialized to $n=1$. In the step S220, the assumed sound speed is initialized. As the initialized assumed sound speed, the data that has been obtained in the process performed in the image generator 18 may be used.

[0057] In the step S230, the assumed sound speed is changed by one step, and data at the resultant sound speed is acquired. To this end, again, the data that has been obtained in the process performed in the image generator 18 may be used.

[0058] In the step S240, a similarity peak is searched in the following frame $n+1$ for each kernel in the frame n , and a peak position and a peak value of the similarity peak are obtained.

[0059] A method for calculating similarity is not limited to a specific one. A cross-correlation method for calculating similarity ranging from 0 to 1 as an inter-frame cross-correlation coefficient between two sets of image data, an SAD method, or an SSD method can be used to calculate similarity. Data used to calculate similarity may be either amplitude images or RF data. The RF data used herein means data containing both amplitude information and phase information.

[0060] The similarity is a value indicating whether or not there is an unchanged portion between images. A high similarity indicates that the portion of interest in images does not change with time. That is, determining similarity shows which portion in a frame corresponds to a certain portion in the previous frame. Determining similarity thus allows the positions of the frames to be calculated.

[0061] In the step S250, for each kernel, the position of the similarity peak is used to determine a movement vector parallel to the tomographic plane (the amount of movement in the tomographic plane), and the value of the similarity peak is used to determine the movement distance perpendicular to the tomographic plane (the amount of movement perpendicular to the tomographic plane).

[0062] The relationship between the peak value and the amount of perpendicular movement is preferably measured (calculated) and tabulated in advance.

[0063] In the step S260, a judgment is made whether or not the above processes have been completed for all the assumed sound speeds. When the above processes have not been completed for all the assumed sound speeds, the control returns to the step S230, and the assumed sound speed is changed by one step to carry out the processes for the changed assumed sound speed.

[0064] When the above processes have been completed for all the assumed sound speeds, in the following step S270, the movement vectors parallel to the tomographic plane and the

movement distances perpendicular to the tomographic plane in each kernel at all the assumed sound speeds are averaged.

[0065] Alternatively, the similarities in each kernel at all the assumed sound speeds may be averaged. That is, similarities may be averaged, and the averaged similarity and the similarity peak are used to determine the movement vector parallel to the tomographic plane and the movement distance perpendicular to the tomographic plane.

[0066] In the step S280, the frame number n is incremented by 1 to $n+1$.

[0067] In the step S290, a judgment is made whether or not the above processes have been completed for all the frames.

[0068] When the above processes have not been completed for all the frames, the control returns to the step S220, and the above processes are carried out for the following frame $n+1$. On the other hand, when the above processes have been completed for all the frames, the processes performed in the frame position calculator 20 are terminated.

[0069] The operation of the display image generator 22 will be described below.

[0070] FIG. 4 is a flowchart showing the contents of processes performed in the display image generator 22.

[0071] First, in the step S300 in FIG. 4, a 3D image is generated by placing each frame in accordance with the amount of movement parallel to the tomographic plane and the amount of movement perpendicular to the tomographic plane determined in each kernel position in each frame.

[0072] In the step S310, typical logarithmic compression is performed on the generated 3D image, and gain/DR (dynamic range)/STC (sensitivity time control (depth weighting))/gray map adjustment and other operations are further performed.

[0073] The display image generated in the display image generator 22 is displayed on the monitor 24.

[0074] As described above, in the present embodiment, RF data or amplitude images generated at a plurality of different assumed sound speeds are used to determine similarity in each portion in each frame.

[0075] Since a plurality of different speckle patterns based on assumed sound speeds are used, similarity can be determined in a stable manner. In particular, since a variety of patterns from low-resolution patterns to high-resolution patterns are uniformly contained, similarity can be determined in a stable, accurate manner.

[0076] Further, although the optimal sound speed in a portion differs from those in other portions, a variety of patterns from low-resolution patterns to high-resolution patterns are similarly contained, similarity can be uniformly determined in any portion. Moreover, since similarity is produced from received data obtained in the same single transmission, the frame rate will not be lowered, and reduction in accuracy due to shift between transmission operations will not occur. Further, when the relationship between the similarity and the probe movement distance is used in freehand-based 3D image reconstruction, the relationship changes with the resolution of speckle. However, even in portions containing a variety of patterns from low-resolution patterns to high-resolution patterns, the relationship using these patterns is the same in any portion, whereby reduction in estimated accuracy due to different resolutions will not occur.

[0077] The processes performed in the frame position calculator 20 are not limited to those described above. Other exemplary processes performed in the frame position calculator 20 will be described below.

[0078] The flowchart in FIG. 5 shows a first variation of processes performed in the frame position calculator 20. In the processes shown in the flowchart in FIG. 3 described

above, the speckle position is set in the first frame, but the speckle position is set in each frame in this example.

[0079] In the step S400 in FIG. 5, the frame number n is initialized to $n=1$.

[0080] In the step S410, speckle areas are searched for a standard image of the frame n , and a kernel having a predetermined size is set in each of the detected speckle areas. The standard image is an image obtained at an ultrasound speed of 1540 [m/sec].

[0081] In the step S420, the assumed sound speed is initialized, and in the step S430, the assumed sound speed is changed by one step.

[0082] In the step S440, a similarity peak is searched in the following frame $n+1$ for each kernel in the frame n .

[0083] In the step S450, for each kernel, a movement vector parallel to the tomographic plane and the movement distance perpendicular to the tomographic plane are calculated.

[0084] In the step S460, a judgment is made whether or not the above processes have been completed for all the assumed sound speeds. When the above processes have not been completed for all the assumed sound speeds, the control returns to the step S430, and the assumed sound speed is changed by one step to carry out the processes for the changed assumed sound speed.

[0085] When the above processes have been completed for all the assumed sound speeds, in the following step S470, the movement vectors parallel to the tomographic plane and the movement distances perpendicular to the tomographic plane in each kernel at all the assumed sound speeds are averaged.

[0086] In the following step S480, the frame number n is incremented by 1 to $n+1$, and in the step S490, a judgment is made whether or not the above processes have been completed for all the frames.

[0087] When the above processes have not been completed for all the frames, the control returns to the step S410, and the processes for the following frame $n+1$ are carried out. When the above processes have been completed for all the frames, the processes performed in the frame position calculator 20 are terminated.

[0088] The flowchart in FIG. 6 shows a second variation of processes performed in the frame position calculator 20. In this example, the speckle initial position is set in the first frame, and the speckle position in each frame is set at a position to which the speckle position in the previous frame is moved in accordance with the movement vector.

[0089] First, in the step S500 in FIG. 6, speckle areas are searched for a standard image of the frame 1, and a kernel having a predetermined size is set in each of the detected speckle areas. The standard image is an image obtained at an ultrasound speed of 1540 [m/sec].

[0090] In the step S510, the frame number n is initialized to $n=1$. In the step S520, the assumed sound speed is initialized, and in the following step S530, the assumed sound speed is changed by one step.

[0091] In the step S540, a similarity peak is searched in the following frame $n+1$ for each kernel in the frame n .

[0092] In the step S550, for each kernel, a movement vector parallel to the tomographic plane and the movement distance perpendicular to the tomographic plane are calculated.

[0093] In the following step S560, a judgment is made whether or not the above processes have been completed for all the assumed sound speeds. When the above processes have not been completed for all the assumed sound speeds, the control returns to the step S530, and the assumed sound speed is changed by one step to carry out the processes for the changed assumed sound speed.

[0094] When the above processes have been completed for all the assumed sound speeds, the control proceeds to the following step S570, and the movement vectors parallel to the tomographic plane and the movement distances perpendicular to the tomographic plane in each kernel at all the assumed sound speeds are averaged.

[0095] In the step S580, the movement vector in each kernel is added to each kernel position in the frame n, and the result is set as each kernel position in the following frame n+1.

[0096] That is, (each kernel position in the following frame n+1)=(each kernel position in the frame n)+(the movement vector in each kernel).

[0097] In the following step S590, the frame number n is incremented by 1 to n+1, and in the following step S595, a judgment is made whether or not the above processes have been completed for all the frames. When the above processes have not been completed for all the frames, the control returns to the step S520, and the processes for the following frame n+1 are carried out. When the above processes have been completed for all the frames, the processes performed in the frame position calculator 20 are terminated.

[0098] As described above, the flow of processes performed in the frame position calculator 20 is not limited to a single flow, but several other flows are conceivable.

[0099] Recent software-based ultrasound apparatus and analog-based high-performance circuit configurations allow image generation at a variety of assumed sound speeds from a received signal obtained in the same single transmission operation. The apparatus in the present invention has a configuration necessary to obtain RF data or images at a variety of assumed sound speeds without shift between frames or not to lower the frame rate.

[0100] In a typical configuration of a conventional ultrasound apparatus, a display image is generated by forming transmission and reception beams at the sound ray positions spaced apart by the distance between elements, producing RF data or amplitude images, then interpolating them for sound rays between elements to produce amplitude data. In recent years, however, there is available a configuration in which transmission and reception beams are formed also for sound rays between elements and then RF data is produced.

[0101] In the apparatus configuration of the present embodiment, random change in speckle phase can be more accurately identified and similarity can be accurately calculated at a resolution in the scan direction higher than or equal to that obtained from the distance between elements, for example, by using high-resolution data in the scan direction so that data whose resolution in the scan direction is higher than or equal to that obtained from the distance between elements are used in the frame position calculator.

[0102] While in the above embodiment, the description has been made of a case where RF data obtained at one type of ultrasound transmission and reception frequency are used, the present invention encompasses a case where RF data obtained at a plurality of different frequencies of a fundamental wave and higher harmonic waves.

[0103] While the ultrasound diagnosis method and apparatus of the present invention have been described in detail, the present invention is not limited to the above example. Various modifications and changes may of course be made to the extent that they do not depart from the spirit of the present invention.

What is claimed is:

1. An ultrasound diagnosis apparatus comprising:
 - a) an ultrasound probe having a plurality of elements arranged therein, the ultrasound probe transmitting ultrasound toward a subject, receiving an ultrasound signal reflected off the subject, and outputting a received signal;
 - b) a device that changes a preset assumed sound speed with respect to an actual sound speed of the ultrasound transmitted toward the subject; and
 - c) a frame position calculation device that determines similarity of each portion between each frame by using speckles in RF data or amplitude images based on two or more of the different assumed sound speeds and calculates frame positions.
2. The ultrasound diagnosis apparatus according to claim 1,
 - 1, wherein the RF data or amplitude images are generated from received data produced by changing the assumed sound speed by multiple steps in a single transmission operation.
3. The ultrasound diagnosis apparatus according to claim 1,
 - 1, wherein the RF data or amplitude images are generated from data whose resolution in a direction in which the elements are arranged is higher than or equal to a distance between the elements.
4. The ultrasound diagnosis apparatus according to claim 2,
 - 2, wherein the RF data or amplitude images are generated from data whose resolution in a direction in which the elements are arranged is higher than or equal to a distance between the elements.
5. An ultrasound diagnosis method comprising:
 - transmitting ultrasound from an ultrasound probe having a plurality of elements arranged therein toward a subject and receiving an ultrasound signal reflected off the subject;
 - changing a preset assumed sound speed with respect to an actual sound speed of the ultrasound transmitted toward the subject; and
 - determining similarity of each portion between each frame by using speckles in RF data or amplitude images based on two or more of the different assumed sound speeds and calculating frame positions.
6. The ultrasound diagnosis method according to claim 5,
 - 5, wherein the RF data or amplitude images are generated from received data produced by changing the assumed sound speed by multiple steps in a single transmission operation.
7. The ultrasound diagnosis method according to claim 5,
 - 5, wherein the RF data or amplitude images are generated from data whose resolution in a direction in which the elements are arranged is higher than or equal to a distance between the elements.
8. The ultrasound diagnosis method according to claim 6,
 - 6, wherein the RF data or amplitude images are generated from data whose resolution in a direction in which the elements are arranged is higher than or equal to a distance between the elements.

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专利名称(译)	超声诊断方法和装置		
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摘要(译)

超声诊断设备包括：超声探头，其中布置有多个元件，超声探头向对象发射超声，接收从对象反射的超声信号，并输出接收信号；相对于向对象发送的超声波的实际声速改变预设的假定声速的装置；帧位置计算装置通过使用RF数据中的斑点或基于两个或更多个不同的假设声速的幅度图像来确定每个帧之间的每个部分的相似度并计算帧位置，从而确定稳定，均匀，准确的相似性不降低帧率的方式。

