



(11)

EP 1 522 875 B1

(12)

EUROPEAN PATENT SPECIFICATION

(45) Date of publication and mention
of the grant of the patent:
21.03.2012 Bulletin 2012/12

(51) Int Cl.:
G01S 15/89 (2006.01) **A61B 8/08** (2006.01)
G01S 7/52 (2006.01)

(21) Application number: **03425639.6**

(22) Date of filing: **30.09.2003**

(54) **A method of tracking position and velocity of object's borders in two or three dimensional digital echographic images**

Methode zur Positions- und Geschwindigkeitsverfolgung eines Objektrandes in zwei- oder dreidimensionalen digitalen echographischen Bildern

Procédé pour suivre la position et la vitesse des contours d'un objet dans des images digitales d'échographie à deux ou trois dimensions.

(84) Designated Contracting States:
**AT BE BG CH CY CZ DE DK EE ES FI FR GB GR
HU IE IT LI LU MC NL PT RO SE SI SK TR**

(43) Date of publication of application:
13.04.2005 Bulletin 2005/15

(73) Proprietors:
• **Esaote S.p.A.**
20100 Milano (IT)
• **Bracco Imaging S.p.A**
20134 Milano (IT)

(72) Inventors:
• **Pedrizzetti, Gianni**
59100 Prato (IT)
• **Tonti, Giovanni**
67039 Sulmona (IT)

(74) Representative: **Karaghiosoff, Giorgio**
Alessandro
Studio Karaghiosoff e Frizzi S.r.l.
Via F. Baracca 1R 4° piano
17100 Savona (IT)

(56) References cited:
WO-A-99/49775 WO-A-03/071950
US-A- 5 515 856 US-A1- 2002 072 674
US-A1- 2003 083 578

• **JACOB G ET AL: "A SHAPED-SPACE-BASED
APPROACH TO TRACKING MYOCARDIAL
BORDERS AND QUANTIFYING REGIONAL LEFT-
VENTRICULAR FUNCTION APPLIED IN
ECHOCARDIOGRAPHY" IEEE TRANSACTIONS
ON MEDICAL IMAGING, IEEE INC. NEW YORK,
US, vol. 21, no. 3, March 2002 (2002-03), pages
226-238, XP001115722 ISSN: 0278-0062**

Note: Within nine months of the publication of the mention of the grant of the European patent in the European Patent Bulletin, any person may give notice to the European Patent Office of opposition to that patent, in accordance with the Implementing Regulations. Notice of opposition shall not be deemed to have been filed until the opposition fee has been paid. (Art. 99(1) European Patent Convention).

EP 1 522 875 B1

Description

BACKGROUND OF THE INVENTION

[0001] The invention relates to a method of tracking position and velocity of objects' borders in two or three dimensional digital echographic images comprising the combination of features according to the preamble of claim 1.

[0002] The automatic detection of borders and their rate of displacement is a fundamental topic in image analysis. The ability to automatically detect borders and their velocity, allows an easy recognition of objects, the improved understanding of its function. In medical imaging the automatic recognition of an organ would eventually facilitate the extraction of objective measurements and automate some diagnostic processes.

[0003] A typical example is given by echocardiography in the imaging of the left ventricle. The possibility of an automatic detection of the endocardial border would give objective measurement of the ventricular volume, in particular its extreme values (at proto-systole and tele-diastole) are commonly used for clinical diagnosis and the relative diagnostic indexed are calculated. In addition, the possibility to visualize the border velocities allows an easier assessment of the regional dynamical properties.

[0004] In general, and certainly in echographic imaging, the development of reliable methods for the automatic border detection is an extremely difficult task that has not received a generally reliable solution. In fact, in clinical practice, borders are drawn manually by the operator over the physiologically relevant frames of a sequence of images.

[0005] A strain rate analysis method in ultrasonic diagnostic imaging is disclosed in WO 02/45587. According to this document strain rate analysis is performed for ultrasonic images in which the spatial gradient of velocity is calculated in the direction of tissue motion. Strain rate is calculated for cardiac ultrasound images in the direction of motion which, for myocardial images, may be either in the plane of the myocardium or across the myocardium. Strain rate information is calculated for a sequence of images of a heart cycle and displayed for an automatically drawn border such as the endocardial border over the full heart cycle. The spatial gradient of velocity used for determining the strain and the displacements of the borders from one frame to a successive one in a sequence of frames uses so called Doppler Tissue Imaging, so called DTI. This technique allows to measure tissue velocity over all points in the ventricular wall. The measurement of velocity itself provides a direct information about the wall motion and helps to uncover abnormalities not immediately observable from the visualization in B-mode. The velocity contains information about either rigid body displacement, shear, and contraction/distension, the latter being immediately related to the myocardial activity. Post processing of the DTI velocity data allows the evaluation of additional quantities, namely

strain-rate and strain, that are strictly related to the regional function. Segmental strain gives a direct evaluation of the degree of contractility of the myocardium during systole, as well as of its relaxation during ventricular filling.

[0006] Nevertheless DTI suffers from a few drawbacks consisting in limitations of the technique. The evaluation of velocity, and to a greater degree when rate and strain are evaluated, requires a higher frame rate with respect to B-mode imaging because velocity is a more rapidly varying function than B-mode displacement. A Doppler signal requires additional processing with respect to the simple echo.

[0007] Doppler tissue imaging suffers further of an intrinsic limitation due to the fact that only the component of velocity along a scanline can be measured. This limitation has several drawbacks. When tissue moves in a direction that is not aligned with the scanline, the Doppler velocity does not reflect the effective tissue kinematics. Only the component of strain and strain rate along the scanline can be evaluated correctly, giving a reduced view of the local deformation state. This limits the application of DTI to the anatomic sites that can be imagined aligned along a scanline. In echocardiography this corresponds essentially to the interventricular septum and to the lateral walls in apical view.

[0008] Document W02003/071950 discloses a method according to the preamble of claim 1.

[0009] An object of the present invention is to provide for a method of tracking position and velocity of objects' borders in two or three dimensional digital echographic images which overcomes the drawbacks of the known tracking methods in reducing the load actually needed for acquiring the usable ultrasound image data and for evaluating, i.e. elaborating the said ultrasound imaging data in order to track the displacement of a border of a moving tissue or a moving object in a sequence of consecutive ultrasound image frames.

[0010] Another object of the present invention is to provide for a method which can lead to more reliable results in tracking the borders of a moving tissue or object on a sequence of consecutive ultrasound image frames.

DISCLOSURE OF THE INVENTION

[0011] The present invention achieves the above mentioned aims with a method of tracking position and velocity of objects' borders in two or three dimensional digital echographic images comprising the combination of steps of the preamble of claim 1 with the steps of the characterizing part of claim 1.

[0012] More precisely transmural cuts consist in defining a line which crosses the border line drawn and passing through one reference point. A physiologically appropriate direction can be chosen, which typically can be the orthogonal direction to the border line at the reference point.

[0013] This operation is made for each image frame

of the sequence of frames and for each reference point chosen. The pixels taken along each transmural line in each of the image frames of the sequence of image frames are placed in columns, each column corresponding to one frame of the sequence of images. In this way the evolution along a transmural cut, can be represented for all instants at once in a two-dimensional space time representation.

[0014] The above disclosed procedure is a reduction of a two dimensional problem applied to a two dimensional image such as a B-mode ultrasound image to a one dimensional problem as a M-mode image.

[0015] The tracking of the border, i.e. of the trace of pixels is carried out along the space-time image using a cross-correlation procedure of the pixel column in the space-time image corresponding to a first image frame with the pixel column in the space-time image corresponding to a successive image frame of the sequence of image frames.

[0016] This technique can be applied to any kind of images in which the geometry of the border line drawn does not require any kind of special reference points to be tracked a priori such as pro example closed border lines as the border line of the cavity of a blood vessel in a cross-section image of the vessel.

[0017] When the object imaged has particular starting and ending points of a border which has a relevance as particular reference points in the motion executed by the border-line of the object, for example in the case of the walls of the endoventricular cavity, then a preventive cycle must be carried out for optimally tracking the border-line of the object along the sequence of image frames.

[0018] According to a further improvement of the above mentioned method when the object has few very representative points the general topology of the border line of the object imaged can be represented by tracking the motion of these few representative points prior to carry out the tracking of at least one or some of the reference points lying on the manually or automatically drawn border-line in each frame of the sequence of image frames.

[0019] These representative points can be for example the starting and ending points of the border line when this is an open one.

[0020] The representative reference points of the border of an imaged object can be also suggested by the physiology when the imaged object is a particular tissue or organ, such as for example the left ventricle.

[0021] Thus prior to carry out the tracking of some or all of the reference points chosen on the manually or automatically drawn border-line of the imaged object along the sequence of image frames the tracking of this few representative reference points is carried out.

[0022] The tracking of this few representative reference points is carried out in a identical way as the one disclosed above for the other reference points on the border-line drawn manually or automatically on the first frame by using the method of transmural cuts for constructing space-time images of each of the few repre-

sentative reference points and determining the displacement of these points in each of the frames of the sequence of image frames by means of cross-correlation between each of the pixel columns with the successive pixel column corresponding to the pixels along the transmural cut across the same representative point in the different image frames of the sequence of image frames.

[0023] The direction of the transmural cuts can be chosen as the orthogonal direction

[0024] According to a further feature after having determined the displacement of the few representative reference points on the border-line of the imaged object in some or in all of the frames of the sequence of image frames, the position and the displacement of the other reference points on the border-lines at each image frame of the sequence of image frames are obtained by rescaling the originally drawn border-line in the first image frame in such a way to obtain in each image frame corresponding to a successive instant a topologically equivalent border line geometry with respect to the original border line. Typically this results in a translation of all points along the original border line.

[0025] This preliminary rescaling allows to keep the representative reference points always in the proper position in all frames of the sequence of image frames by rearranging the other reference points so that the representative reference points maintains the same meaning relatively to the object in all frames of the sequence of image frames.

[0026] Thus in a preferred embodiment the complete method according to the invention comprises the following steps:

- a) Acquiring a sequence of at least two consecutive ultrasound image frames of a moving tissue or a moving object which ultrasound image frames are timely separated by a certain time interval;
- b) Tracing a border line over one single first frame either manually or with the help of an automatic border drawing algorithm;
- c) Tracking the position displacements of one or more eventually present representative reference points over the entire sequence of consecutive image frames;
- d) Rescaling the border line drawn on the first image frame at least for some or for each of the following image frames of the sequence of image frames according to the corresponding position tracked of the representative reference points;
- e) Defining a certain number of further reference points distributed along the border line on the first image frame and falling on the said border line;
- f) Tracking the position of each point independently from the others along the sequence of image frames;
- g) Tracking of the position of the representative reference points and of the other reference points being carried out by
- h) for each point independently and in each of the

image frames of the sequence of image frames defining a transmural cut line consisting in a line which crosses the border line drawn and passing through the said reference point;

i) the pixels taken along each transmural cut line in each of the image frames of the sequence of image frames are placed in columns, each column corresponding to one frame of the sequence of images for representing the evolution along a transmural cut line, for all instants at once in a two-dimensional space time representation;

j) the tracking of the border. i.e. of the trace of pixels along each transmural cut line is carried out along the space-time image using a cross-correlation procedure of the pixel column in the space-time image corresponding to a first image frame with the pixel column in the space-time image corresponding to a successive image frame of the sequence of image frames.

[0027] According to an improvement in both cases disclosed above when images are poor with a low signal-to-noise ratio the space-time representation along the transmural cuts can be built using a line for the transmural cut with a thickness larger than that of a single pixel and by extracting the average value across such a thickness.

[0028] The above mentioned method can be further developed for carrying out a surface border tracking three dimensional imaging.

[0029] The method according to the said development comprises the following steps:

1) Acquiring a sequence of three-dimensional ultrasound imaging data sets, each three-dimensional data set being acquired with a predetermined time interval from the previous one;

m) Defining at least a principal section plane of each three dimensional data set along one chosen direction for obtaining a sequence of two dimensional image frames along the said section plane;

n) Drawing a border line of the object imaged either manually or automatically on the first two dimensional image frame of the sequence of two dimensional image frames taken along the said section plane;

o) Carrying out the tracking steps c) to j) previously disclosed for the two dimensional sequence of image frames;

p) For each three dimensional data set of the sequence of three dimensional datasets defining a pre-established number of further secondary section planes crossing the at least one, preferably all the principal section planes, the said secondary section planes being spaced apart one from the other along a predetermined direction and dividing the object represented by each three dimensional data set of the sequence of three-dimensional data sets in slices.

q) For each secondary section plane in the sequence

of three dimensional data sets constructing the corresponding sequence of image frames relative to the said secondary section plane;

r) For each sequence of two dimensional image frames determining a guess border line in one single frame, by letting the border line passing across the intersection points with the principal section planes;

s) Tracking the said guess border line by detecting a new border by applying the method steps according to c) to j) or e) to j) by substituting the time coordinate in the said disclosed steps with the spatial coordinate along the said guess border line by

t) defining a certain number of transmural cuts on the single image of the sequence of images along the guess border line;

u) identifying the pixels along the said transmural cuts and placing the pixels along each transmural cuts side by side for constructing a two dimensional image where the horizontal axis indicates the spatial coordinate along the guess border line;

v) carrying out the cross correlation between each of the consecutive pixel columns in the said two dimensional image and thus tracking the border line in one frame for each of the sequences of two dimensional image frames corresponding to each of the secondary section planes.

[0030] According to a further improvement one or more further principal section planes can be defined along each of which further section planes the methods steps 1) to o) are carried out.

[0031] In a preferred embodiment two orthogonal principal section planes are chosen for carrying out the above mentioned method steps, the crossing line of the two principal section planes defining a preferred direction of the said planes.

[0032] The said direction can be chosen as suggested by the topological or functional feature of the object imaged.

[0033] Considering ultrasound images of a biological tissue or of an organ such as for example the heart the said direction can be suggested by physiological reasons. For example this physiologically relevant direction can be chosen as the cut across a central vertical plane such as the ventricle axis.

[0034] In order to better define the share of secondary section planes cutting the principal section planes, the method according to the present invention comprises the steps of defining bounds or limits for a distance range within which the share of the said secondary section planes is defined.

[0035] Preferably a topological or physiological relevant direction is chosen, particularly the same direction defined for determining the principal section planes, along which direction bounds are determined for the ends of a distance range within which the share of secondary section planes at least transversal, particularly perpendicular to the said relevant direction is determined.

[0036] Still according to a further embodiment, when determining the first guess border line, this one is determined as a physiologically relevant line passing through the reliable points.

[0037] According to the present border tracking method the correct border is determined along a sequence of two dimensional or three dimensional ultrasound image data and the correct border for each image frame can be displayed overlaid on the displayed image frame as an highlighted line characterized by a color which is different from the grey-scale B-mode image displayed.

[0038] A different evaluation of the velocity vector can be obtained by applying two dimensional-correlation techniques or a specific optical flow technique particularly developed for ultrasound image data of moving objects.

[0039] The said velocity estimation method can be carried out in combination with the above disclosed method for tracking the border of the imaged moving object.

[0040] The said method is an adaptation of known method so called OPTICAL FLOW methods, like a known method so called PIV method used in fluid dynamics.

[0041] Thus in displaying the B-mode images the border tracked can be drawn as a line as disclosed above and the velocity vectors of the border taken at certain number of points of the said border line are displayed as arrows having a different color as the border line and the direction of the velocity vector and a length corresponding to the modulus of the velocity vector in the image plane of the two dimensional image displayed. By means of the method according to the present invention a different approach for tracking borders of a moving object in two and three dimensional ultrasound imaging is provided where the borders are not "detected", rather they are "tracked", i.e. followed in time, starting from one reliable existing instantaneous trace that is commonly -but not necessarily- manually drawn by the experienced operator over one single frame. Using this approach all the ambiguousness that are present in a pure detection approach are cleared, the original trace is followed in time by searching the maximum likelihood over its neighborhood in the following frames. The tracking technique for each single point is approached using a method based on transmural cuts that is similar to that introduced in the document PCT/IT02/00114 filed on 27.02.2002. Afterward the velocity on the tracked borders are estimated on the basis of the same maximum likelihood between two consecutive frames.

[0042] The automatic tracking method disclosed here allows the tracking of a border on a sequence of two-dimensional or three-dimensional images, and the evaluation of the velocity vector field on such borders. In principle, the border could be tracked on the basis of the velocity vector only, however a tracking procedure is a result of the summation (time integration) of the estimated velocities and is prone to an error growth in presence of small incorrect estimates. This approach reduces the two- or three-dimensional tracking to a combination of one-dimensional tracking problems along the single top-

ological relevant direction (typically the orthogonal to the border), that can be much better controlled and made accurate. On the opposite, the accurate tracking result is employed to improve the estimates of the velocity vector.

[0043] The result of this procedure is the automatic definition of the borders displacement and velocity over all frames of a 'sequence of images, starting from the border traced on a single image.

[0044] Eventually, the found borders information will be used to evaluate some geometric properties, like volume, area, or sizes, of the organ. The border kinematics (tracking + velocity) allows to estimate global quantities (like volumes, lengths) as well as local phenomena (like rotations, strain) in a unique approach.

BRIEF DESCRIPTION OF THE DRAWINGS

[0045]

Figure 1 illustrates an echographic image of the left ventricle, in long axis view (from the apex to the mitral plane), extracted from an echocardiographic recording (58 frames, 2 cycles) with an endocardial border (white) and the instant border velocity (white arrows), Figure 2 illustrates an echographic image of the left ventricle, in short axis view (transversal section), extracted from an echocardiographic recording (49 frames, 2 cycles) with a "closed" endocardial border (white) and the instant border velocity (white arrows). Figure 3 illustrates an echographic image of the left ventricle, in long axis view. The traced endocardial border implicitly defines the starting and final points and the mitral plane. The position of the transmural cuts, passing from the edge points and normal to the transmittal plane, are indicated.

Figure 4 illustrates a space-time representation, where space is along a transmural cut, of the echographic images sequence. The transmural cut is taken as for the starting point in figure 3. The time evolution of the starting point, tracked automatically, is reported.

Figure 5 illustrates an echographic image of the left ventricle, in long axis view, during diastole (left) and systole (right). The original endocardial border just rescaled on the basis of the mitral plane displacement is shown. The instantaneous transmural cuts on each of the originally points are also drawn.

Figure 6 illustrates a schematic view of an example of cutting a three-dimensional dataset with two orthogonal planes, having one common direction, to get two two-dimensional images

Figure 7 illustrates a schematic view of an example of cutting a three-dimensional dataset with transversal planes that are orthogonal to the principal planes like those employed in figure 6.

Figure 8 illustrates slices on a three-dimensional echographic dataset of the left heart. The left ventri-

cle border is known on the vertical image. The border at the intersection with the horizontal slices represent the starting points for tracking the border on the horizontal images.

Figure 9 illustrates an horizontal slice on a three-dimensional echographic dataset of the left heart. The starting points and a circular first guess border are indicated.

DETAILED DESCRIPTION OF THE DRAWINGS AND OF THE METHOD

Two-dimensional imaging

[0046] The method steps according to the present invention are firstly describe with reference to a two dimensional case. A sequence of two dimensional B-mode image frames is acquired. The frames are acquired at pre-determined time interval one form the other.

[0047] Consider a sequence of two-dimensional (2D) images; mathematically, this is a three-dimensional (3D) information that is 2D in space and 1D in time. Consider that the images contain one organ/object or part of it, that changes its position and shape in time, of which organ we want to trace the border kinematics at all instants.

[0048] The method according to the present invention comprises a first step which consist in tracing the border over one single frame by defining a border line.

[0049] A border is traced, manually or by another manual or automatic procedure, over one arbitrary frame. Such border is then defined as a sequence of N points, defined by their coordinate pairs (x_i, y_i) with $i=1...N$ in the two dimensional image plane.

The result of this step is illustrated in figure 1 and 2. Figure 1 illustrates an image of the left ventricle where the endocardial border points are traced from one side of the mitral annulus to the other side of the same mitral annulus. Figure 2 illustrates an example in which the border is a closed one where the Nth point connects to the first one.

[0050] Referring now to a particular case like the one illustrated in figure 1, where the border has a staring and an ending point, the method according to the invention provides for a second step of tracking the most representative reference point of the border line drawn in the first image frame.

[0051] According to this step, the general topology of the object border is reproduced on all the images by tracking the motion of a few representative points. These are commonly the starting and final points of the border when this is an open one. In specific cases additional reference points can be added to improve the first evaluation of the region about which the border must be sought.

[0052] The displacement of the representative reference points along one or more specific directions is evaluated. Figure 3 shows the reference points for a left ventricle (in long axis view) that are the starting and final points of the originally traced border. In this case, the

physiology suggests to track the motion of these points in the direction instantaneously orthogonal to the mitral plane (that is defined by these points).

[0053] The tracking along a specified direction is performed by using the method of transmural cuts as follow. A line crossing the wall, passing through the point, and directed along the physiologically appropriate direction is drawn; in the case shown in figure 3 the appropriate direction is orthogonal to the mitral plane. In general two orthogonal direction can be employed. The pixels taken along the chosen direction line(s) are placed in columns, each column corresponding to one frame of the sequence of images. In this way the evolution along a line can be represented for all instants at once in a two dimensional space-time representation (sometime referred as M-mode representation) where one axis is the distance along the line and the other axis is the time. An example of such a representation is shown in figure 4.

[0054] In the case of poor images with a low signal to noise ratio the space time representation can be built using a line for the transmural cut with a thickness larger than that of a single pixel and extracting the average value across such a thickness.

The border tracking is then performed along the space-time image.

Tracking along the 2D space-time image

[0055] The tracking procedure is a procedure for following a border along one direction in a two-dimensional image like that in figure 4 starting from a known position at one instant.

[0056] Let us call x the horizontal direction and y the vertical direction, and indicate with x_i , $i=1...N$, where N is the number of columns in the image. The tracking is given by determination of a discrete sequence of real numbers $y_i=y(x_i)$, starting from a known point y_k corresponding to the columns x_k .

[0057] This is a one dimensional tracking problem that can be solved with several possible standard methods. One method is reported here for giving completeness to the whole invention that can, however, employ also different techniques for this specific task when suggested by the specific imaging employed.

[0058] The displacement from the known point y_k to the point y_{k+1} can be estimated by evaluating the cross-correlation between the entire column at x_k with the entire column at x_{k+1} . The cross-correlation function will present a maximum, the position of the maximum gives the value of the vertical displacement required to maximize the similarity between the two columns, therefore y_{k+1} is estimated by adding such a displacement to y_k . This procedure is repeated between all pairs of nearby columns and the result is an estimate of the entire border y_i , $i=1...N$.

[0059] In this procedure it is convenient to employ windowing techniques that avoid side effects given by the two ends of the finite size columns. When applicable, it

is also convenient to make use of the periodicity of the signal along x in order to perform the method in Fourier space.

[0060] The first estimate is improved by applying the same procedure recursively on increasingly reduced spatial width about the previously found border.

This first estimate y_i can be further improved. To this aim a subset of the image is extracted by taking a few points above and below the first estimate y_i , and a new image whose center corresponds to the sequence y_i is generated. A snake procedure like the one described in Blake A., Yuille A. *Active Vision* MIT press, 1992., is employed to follow, in the new image, the image brightness level that passes through the fixed point y_k . As a result the estimation of y_i , $i=1...N$ is refined.

[0061] As it will become clear in the following description the tracking technique is a unique procedure that is common to different steps of the method according to the present invention.

[0062] As applied to the above mentioned step of the method according to the present invention, the result of this preliminary tracking procedure is the position and displacement, at all instants, of the most representative reference points along the predefined direction, or the vector combination when two directions are employed.

[0063] After this, all the other points of the original border are rescaled at each instant in order to get, at each instant a topologically equivalent border geometry. Typically, like in the example of figure 2, all the points are translated along the original curve.

[0064] This preliminary rescaling procedure permits to keep the reference points always at the proper position in all the frames, and to rearrange the other points so that the reference maintains the same meaning in all the frames.

[0065] The present step of tracking the most representative reference points such as the starting and ending point of a border line can be avoided when the specific geometry does not require or have any representative reference point to be tracked a priori. One example where this step can be avoided is given by the closed geometry in figure 2.

[0066] After having carried out the tracking of the most representative reference points if these points are present or in place of the said tracking step the method according to the invention provides for a further step consisting in the tracking of all the other reference point on the border line drawn manually or automatically in the first step on a first two dimensional image frame of the sequence of image frames.

[0067] For each point, independently, the tracking along a specified direction is performed by using the method of transmural cuts as follow. A line crossing the wall, passing through the point, and directed along the physiologically appropriate direction is drawn, this operation is made for each instant/frame of the sequence of image frames because the points are not fixed in time but they have been previously rescaled at each instant

accordingly with the instantaneous displacement of the reference points. In most cases, like in the case shown in figure 5, the appropriate direction is taken at each instant as orthogonal to the rescaled border. The pixels taken along each transmural line are placed in columns, each column corresponding to one frame of the sequence of images. In this way the evolution along a transmural cut, that is not fixed in all frames time but is slightly modified accordingly to the rescaling, can be represented for all instants at once in a two-dimensional space time representation analogous to that shown in figure 4.

[0068] In the case of poor images with a low signal-to-noise ratio the space time representation can be built using a line for the transmural cut with a thickness larger than that of a single pixel and extracting the average value across such a thickness.

[0069] The border tracking is then performed along the space-time image using the same technique employed in the step of tracking the representative reference points and disclosed above in a detailed manner.

[0070] The result of this step is the position, at all instants, of all the points along the predefined direction, or the vector combination when two directions are employed. At this stage all the original points have been tracked in time, each one independently, and we have a new border tracked over all frames.

[0071] It can be useful, especially in poor quality images, to improve the estimate by including a spatial coherence in the tracked border. This can be done by verifying the likelihood of the tracking between neighboring points and correcting the eventual discrepancies with appropriate filters or validation methods.

[0072] As an additional procedure the method according to the present invention can be provided in combination with a procedure for determining the instant border line velocity vector for each one of the reference points defined on the border line as tracked on each two dimensional frame.

[0073] For each point, independently, the velocity vector can be known when two direction (three for three-dimensional image) are employed for displacing it. When a single direction is employed, the complete velocity vector can be evaluated by selecting additional direction for the transmural cuts on the already displaced point and evaluating the velocity along the additional direction.

[0074] In the case of poor images with a low signal-to-noise ratio the space time representation can be built using a line for the transmural cut with a thickness larger than that of a single pixel and extracting the average value across such a thickness.

[0075] Alternatively, the complete velocity vector can be evaluated by a two-dimensional correlation technique or a specific optical flow technique adapted to the particular case of ultrasound imaging B-mode data. The two-dimensional result can then be improved by imposing its accordance with the previous estimate obtained for one component from the transmural cut approach. Results of the entire procedure are shown, for one frame, in figure

1 and 2.

Three-dimensional imaging

[0076] The same steps described for the analysis of two-dimensional imaging can be employed for the border tracking in three-dimensional imaging. Such an extension is straightforward by using the previous steps in an appropriate combination, and substituting, in one case, the time direction with one spatial direction. Eventually no additional manual intervention is necessary with respect to what is done in two-dimensions, i.e. the indication of the border in one 2D frame.

[0077] A sequence of three-dimensional (3D) datasets is mathematically a four-dimensional (4D) information that is 3D in space and 1D in time. Consider that the images contain one organ/object or part of it, that changes its position and shape in time, of which organ it is desired to trace the border at all instants, the border now being a sequence of two-dimensional surfaces.

[0078] As a first step the method according to the present invention provides to choose one principal section plane which cuts to the three-dimensional dataset, and to apply the entire two-dimensional technique disclosed above on such plane.

[0079] The principal section plane of the 3D dataset is one plane, preferably along a physiologically relevant direction. Cutting the 3D datasets of the sequence of 3D datasets with this plane furnishes one sequence of 2D images.

[0080] Figure 6 illustrates the cutting of a three-dimensional data set of ultrasound image data of the object 0 with two orthogonal principal section planes 1 and 2 oriented in the vertical direction.

[0081] For each principal section plane the entire tracking procedure as disclosed above for the sequence of two dimensional images is applied to this two-dimensional sequence of images taken on the principal section planes in order to track the border and evaluate the velocity on such principal section plane. This border is the signature of the sought border kinematics on the plane.

[0082] The above steps can be repeated with more than one or two principal section planes to improve the reliability of following steps in poor quality images.

[0083] After having carried out the above mentioned step a further step is carried out consisting in defining secondary section planes to the three-dimensional dataset, and applying the two-dimensional technique on single frames substituting the time direction with one spatial direction.

[0084] The previous step allows to define the bounds of the surface border. For this, one direction is chosen over the plane cut used in the previous step, preferably a physiologically relevant one (like the ventricle axis), and, for each instant, evaluate the upper and lower bounds along such direction of the border found in the previous step.

[0085] The range between these limits, at each instant,

is further divided in M internal points, and the 3D dataset is cut in correspondence of such M points, with M secondary section planes that are orthogonal to the chosen direction as indicated with 3, 4, 5 in figure 7. By means of the said secondary section planes the corresponding M sequences of 2D images are constructed.

[0086] Successively, for each sequence, a reliable border in one single frame is defined, commonly the same frame used when the borders are drawn manually during the previous step relative to the principal section planes.

[0087] In each of such single M frames, the border now contains one or more reliable points, at the intersection with the principal section plane or planes 1, 2 and that come from the border(s) determined in the previous step relative to the principal section planes as illustrated in fig. 8 and indicated by R1, R2, R3, R4. A first guess border is constructed as a physiological relevant one passing through these reliable points R1, R2, R3, R4. An example of the said guess border on a secondary section plane is illustrated in the example of figure 9. Here the two dimensional image on a secondary section plane is illustrated together with the two reliable points R1 and R2. The guess border passing through the said two reliable points R1 and R2 is given by given by a circle in the transversal images of the left ventricle.

[0088] A new border is now detected by the same procedure used for a single transmural cut as disclosed in the previous chapter for the two dimensional case, this time however, substituting the time coordinate with the spatial coordinate along such first guess border as follows. Make a number of transmural cuts on the single image along the guess border, place the pixel found along each cut side by side in a new two-dimensional image and obtain a new image, like that in figure 4, where the horizontal axis does not indicate the time coordinate but the spatial coordinate along the tentative border. As a result the correct border is tracked in one frame for each of the M sequences.

[0089] The above mentioned procedure is applied on all the sequences obtained from the appropriate cutting of the three-dimensional dataset according to each secondary section plane defined. The tracking technique disclosed above in the previous chapter of the two dimensional ultrasound imaging is applied to each of the M sequences taking as a starting, reliable, border that found on one frame in the step relating to the secondary section planes. The resulting M borders will define the complete surface border.

[0090] Similarly to the two dimensional case discussed above also in the three-dimensional imaging case the instantaneous velocity vector for a certain number of predefined points on the border surface can be calculated by using the same technique disclosed of the two dimensional case. The two dimensional technique disclosed above is used here by substituting the two dimensional estimate with a three-dimensional estimate of velocity.

[0091] When the tracking procedure is insufficient to define the entire velocity vector, this is done by selecting

additional direction for the transmural cuts on the already displaced point and evaluating the velocity along the additional direction.

[0092] Alternatively, this is done by using a three-dimensional correlation or optical flow technique, in place of the two-dimensional one for evaluating the three-dimensional velocity vector.

Claims

1. A method of tracking position and velocity of objects' borders in two or three dimensional echographic images comprising the following steps:

Acquiring a sequence of at least two consecutive ultrasound image frames of a moving tissue or a moving object which ultrasound image frames are timely separated by a certain time interval. Automatically or manually defining a certain number of reference points of a border of a moving tissue or object at least on a first image frame of the sequence of image frames acquired;

Automatically tracking the border of the moving tissue or object in the at least one further following frame by determining the new position of the reference points of the border in at least one following image frame of the sequence of image frames by estimating the position of the said reference points in the said at least following image frame of the sequence of image frames on the basis of the ultrasound image data of the acquired sequence of image frames.

the sequence of image frames acquired is a sequence of consecutive B-mode, grey scale ultrasound images;

On a first frame a border line is drawn either manually or by means of an automatic border detection algorithm the border being defined by a trace of pixels of the image frame coinciding with the said border line;

The original trace of pixels coinciding with the manually or automatically drawn border line is followed in time, i.e. in the at least one following image frame by searching the maximum likelihood of the trace of pixels in the following image frame with the trace of pixels in the first or timely previous image frame of the sequence of image frames by analyzing the image pixels in the neighbourhood of the said trace of pixels;

the tracking of the border line is carried out by defining a certain number of reference points on the manually or automatically drawn border line on the first image frame and by using the method of the so called transmural cuts.

the said transmural cuts consist in defining for each reference point a line which crosses the border line drawn on a first image frame and

each of which lines passing through one reference point; each transmural cut line having a definite direction, which typically can be the orthogonal direction to the border line at the reference point;

carrying out the above mentioned step of defining transmural cuts for each image frame of the sequence of frames and for each reference point chosen;

the pixels taken along each transmural line in each of the image frames of the sequence of image frames being then placed in columns, each column corresponding to one frame of the sequence of images, forming a two-dimensional space-time representation of the evolution of the position of each reference point along the corresponding transmural cut;

the tracking of the border line i.e. of the trace of pixels, is carried out for each reference point defined on the said border line along the corresponding two-dimensional space-time image using a cross-correlation procedure of the pixel column in the space-time image corresponding to a first image frame with the pixel column in the space-time image corresponding to a successive image frame of the sequence of image frames,

the method

comprising steps for determining the border line instant velocity on each image frame of the sequence of image frames, whereby a first estimation of the

instant velocity is determined for each reference point on the border line by dividing the displacement vector of each of the reference point from a first to a following image frames of the sequence of image frames by the time interval occurred between the said first and said following image frames,

And which method is further **characterized by** the steps of

Determining the components of the velocity vector on each of the image frames of the sequence of image frames for each of the reference points on the border-line by selecting additional direction for the transmural cuts on the already displaced point and evaluating the velocity along the additional direction by applying the said method steps of the so called transmural cuts along the said additional direction required to evaluate the complete velocity vector;

The evaluation of each of the component(s) of the velocity vector along each direction, the total number of components being two for two-dimensional imaging and being three for three-dimensional imaging ;

being carried out according to the following steps:

- aa) For each reference point, on each image frame of the sequence of image frames, a transmural cut consisting in a line which crosses the tracked point and directed along the direction where the additional component of velocity is evaluated, orthogonal to the direction for the other components of the velocity vector. 5
- bb) the pixels taken along each transmural cut line in each of the image frames of the sequence of image frames are placed in columns for all instants at once in a two-dimensional space time representation; 10
- cc) the evaluation of the velocity component along the chosen direction is carried out along the space-time image using a cross-correlation procedure of the pixel column in the space-time image, the said velocity being given by the ratio of the column-wise displacement of the correlation maximum and the time interval between the corresponding frames. 15
2. A method according to claim 1, **characterised in that** it is applied to closed border lines. 25
 3. A method according to one or more of the preceding claims in combination with objects imaged having at least one or more representative reference points in particular a starting and an ending point of a border which having a relevance as particular reference points in the motion executed by the border-line of the object, 30
characterised in that prior of carrying out the tracking of all the reference points defined on the border line drawn on a first image frame of the sequence of at least two image frames a preventive tracking cycle of only the representative reference points is carried out according to the method of one or more of claims 1 to 2. 35 40
 4. A method according to claim 3, **characterised in that** the tracking of the representative reference points is carried out by using the method of transmural cuts for constructing space-time images of each of the representative reference points and determining the displacement of these points in each of the frames of the sequence of image frames by means of cross-correlation between each of the pixel columns with the successive pixel column corresponding to the pixels along the transmural cut across the same representative reference point in the different image frames of the sequence of image frames. 45 50
 5. A method according to claim 3 or 4, **characterised in that** after having determined the displacement of the representative reference points on the border- 55
- line of the imaged object in some or in all of the frames of the sequence of image frames, the position and the displacement of the other reference points on the border-lines at each image frame of the sequence of image frames are obtained by rescaling the originally, manually or automatically drawn border-line in the first image frame in such a way to obtain in each image frame corresponding to a successive instant a topologically equivalent border line geometry with respect to the original border line and to keep the representative reference points always in the proper position in all frames of the sequence of image frames by rearranging the other reference points so that the representative reference points maintains the same meaning relatively to the object in all frames of the sequence of image frames.
6. A method according to one or more of the preceding claims **characterised by** the following steps:
 - a) Acquiring a sequence of at least two consecutive ultrasound image frames of a moving tissue or a moving object which ultrasound image frames are timely separated by a certain time interval;
 - b) Tracing a border line over one single first frame either manually or with the help of an automatic border drawing algorithm;
 - c) Tracking the position displacements of one or more eventually present representative reference points over the entire sequence of consecutive image frames;
 - d) Rescaling the border line drawn on the first image frame at least for some or for each of the following image frames of the sequence of image frames according to the corresponding position tracked of the representative reference points;
 - e) Defining a certain number of further reference points distributed along the border line on the first image frame and falling on the said border line;
 - f) Tracking the position of each point independently from the others along the sequence of image frames;
 - g) Tracking of the position of the representative reference points and of the other reference points being carried out by
 - h) for each point independently and in each of the image frames of the sequence of image frames defining a transmural cut line consisting in a line which crosses the border line drawn and passing through the said reference point;
 - i) the pixels taken along each transmural cut line in each of the image frames of the sequence of image frames are placed in columns, each column corresponding to one frame of the sequence of images for representing the evolution

- along a transmural cut line, for all instants at once in a two-dimensional space time representation;
- j) the tracking of the border. i.e. of the trace of pixels along each transmural cut line is carried out along the space-time image using a cross-correlation procedure of the pixel column in the space-time image corresponding to a first image frame with the pixel column in the space-time image corresponding to a successive image frame of the sequence of image frames.
7. A method according to one or more of the preceding claims **characterised in that** in combination of images of poor quality, i.e. with a low signal-to noise-ratio, the space-time representation along the transmural cuts is built using a line for the transmural cut with a thickness larger than that of a single pixel and by extracting the average value across such a thickness.
8. A method according to one or more of the preceding claims **characterised in that** it is applied for carrying out a surface border tracking in three-dimensional imaging and comprising the following steps:
- l) Acquiring a sequence of three-dimensional ultrasound imaging data sets, each three-dimensional data set being acquired with a predetermined time interval from the previous one;
- m) Defining at least a principal section plane of each three dimensional data set along one chosen direction for obtaining a sequence of two dimensional image frames along the said section plane;
- n) Drawing a border line of the object imaged either manually or automatically on the first two dimensional image frame of the sequence of two dimensional image frames taken along the said principal section plane or each of the said principal section planes;
- o) Carrying out the tracking steps c) to j) previously disclosed for the each sequence of two-dimensional image frames for each corresponding principal section plane;
- p) For each three-dimensional data set of the sequence of three-dimensional datasets defining a preestablished number of further secondary section planes crossing the at least one, preferably all the principal section planes, the said secondary section planes being spaced apart one from the other along a predetermined direction and dividing the object represented by each three-dimensional data set of the sequence of three-dimensional data sets in slices.
- q) For each secondary section plane in the sequence of three dimensional data sets constructing the corresponding sequence of two-dimensional image frames relative to the said secondary section plane;
- r) For each sequence of two-dimensional image frames relatively to each secondary section plane determining a guess border line in one single frame, by letting the guess border line passing across the intersection points of the corresponding secondary section plane with the border line drawn on the principal section plane or of the principal section planes;
- s) Tracking the said guess border line by detecting a new border by applying the method steps according to c) to j) or e) to j) by substituting the time coordinate in the said disclosed steps with the spatial coordinate along the said guess border line by
- t) defining a certain number of transmural cuts on the single image frame of the sequence of images frames corresponding to each secondary section plane along the guess border line;
- u) identifying the pixels along the said transmural cuts and placing the pixels along each transmural cuts side by side for constructing a two-dimensional image where the horizontal axis indicates the spatial coordinate along the guess border line;
- v) carrying out the cross correlation between each of the consecutive pixel columns in the said two dimensional image and thus tracking the border line in one frame for each of the sequences of two-dimensional image frames corresponding to each of the secondary section planes.
9. A method according to claim 8, **characterised in that** one or more further principal section planes can be defined along each of which further section planes the methods steps 1) to o) are carried out.
10. A method according to claims 8 or 9, **characterised in that** two orthogonal principal section planes are chosen for carrying out the above mentioned method steps, the crossing line of the two principal section planes defining a preferred direction of the said planes.
11. A method according to one or more of the preceding claims 8 to 10, **characterised in that** in order to better define the group of secondary section planes cutting the principal section planes, the following steps are provided: defining bounds or limits for a distance range within which the group of the said secondary section planes has to be defined.
12. A method according to claim 11, **characterised in that** a direction along which the secondary section planes are distributed is chosen, which is the same direction defined for determining the principal sec-

tion planes, along which direction bounds are determined for the ends of a distance range within which the group of secondary section planes are defined and which secondary section planes are at least transversal, particularly perpendicular to the said direction.

13. A method according to one or more of the preceding claims the correct border line tracked is displayed overlaid on the corresponding displayed image frame as an highlighted line **characterized by** a colour which is different from the grey-scale B-mode image displayed.

Patentansprüche

1. Verfahren zur Nachverfolgung von Position und Geschwindigkeit von Objektgrenzen in zwei- oder dreidimensionalen echographischen Bildern, bestehend aus den folgenden Schritten:

- Erfassung einer Sequenz von mindestens zwei aufeinander folgenden Ultraschall-Einzelbildern von sich bewegendem Gewebe bzw. von einem sich bewegenden Objekt, wobei die einzelnen Ultraschall-Einzelbilder in einem bestimmten Zeitintervall zeitlich voneinander getrennt sind;
- automatische oder manuelle Festlegung einer bestimmten Anzahl von Bezugspunkten von einer Grenze eines sich bewegenden Gewebes bzw. eines Objektes, zumindest auf dem ersten Einzelbild der aufgenommenen Bildsequenz;
- Automatische Nachverfolgung der Grenze des sich bewegenden Gewebes oder Objekts in dem wenigstens einen nachfolgenden Einzelbild durch Bestimmung der neuen Lage der Referenzpunkte auf der Grenze in wenigstens einem folgenden Einzelbild aus der Bildsequenz durch Schätzung der Position der Referenzpunkte in dem wenigstens einen folgenden Bild der Bildsequenz auf Basis der Ultraschallbilddaten der aufgenommenen Bildsequenz;
- wobei die Sequenz der erfassten Einzelbilder eine Abfolge von aufeinander folgenden B-Mode-Graustufen-Ultraschallbildern ist; in einem ersten Einzelbild wird entweder manuell oder durch einen automatischen Grenzerkennungsalgorithmus eine Grenzlinie gezeichnet, wobei die Grenze durch eine Spur von Bildpunkten des Einzelbildes festgelegt wird, welche mit der Grenzlinie zusammenfällt;
- die ursprüngliche Spur von Bildpunkten, welche mit der manuell oder automatisch gezogenen Grenzlinie zusammenfällt, wird über die Zeit nachverfolgt, indem bei wenigstens einem der folgenden Einzelbilder die größtmögliche Ähn-

lichkeit einer Spur von Bildpunkten in dem nachfolgenden Einzelbild mit der Spur von Bildpunkten in dem ersten oder einem zeitlich vorherliegenden Einzelbild der Bildsequenz **dadurch** ermittelt wird, dass die Bildpunkte des Bildes in der Nachbarschaft der Spur von Bildpunkten Bildpunkte analysiert werden;

- die Nachverfolgung der Grenzlinie erfolgt durch Festlegung einer bestimmten Anzahl von Referenzpunkten auf der manuell oder automatisch auf dem ersten Einzelbild gezogenen Grenzlinie und durch Anwendung des Verfahrens der sogenannten transmuralen Schnitte;
- die transmuralen Schnitte bestehen darin, dass für jeden Bezugspunkt eine Linie festgelegt wird, welche die auf dem ersten Einzelbild gezogene Grenzlinie überschreitet, wobei jede dieser Linien durch einen Bezugspunkt verlaufen; jede transmurale Schnittlinie weist dabei eine bestimmte Richtung auf, die typischerweise orthogonal zur Grenzlinie am Referenzpunkt verlaufen kann;
- Durchführung des vorstehend beschriebenen Schrittes der Festlegung transmuraler Schnitte für jedes Einzelbild aus der Bildsequenz und für jeden ausgewählten Bezugspunkt;
- die entlang jeder transmuralen Linie in jedem der Einzelbilder aus der Bildsequenz erfassten Bildpunkte werden in Spalten angeordnet, wobei jede dieser Spalten einem Einzelbild aus der Bildsequenz zugeordnet ist, wodurch eine zweidimensionale Raum-Zeit-Koordinaten-Abbildung von der Positionsänderung jedes Bezugspunkts entlang der zugehörigen transmuralen Schnittlinie gebildet wird;
- die Nachverfolgung der Grenzlinie, also der Spur der Bildpunkte, erfolgt für alle festgelegten Referenzpunkte auf der Grenzlinie entlang der entsprechenden zweidimensionalen Raum-Zeit-Koordinaten-Abbildung durch ein Kreuzkorrelationsverfahren für die Bildpunktspalte aus der dem ersten Einzelbild entsprechenden Raum-Zeit-Koordinaten-Abbildung mit der Bildpunktspalte aus der Raum-Zeit-Koordinaten-Abbildung, die einem nachfolgenden Einzelbild aus der Bildsequenz entspricht;
- das Verfahren beinhaltet dabei Schritte zur Bestimmung der Grenzlinien-Momentangeschwindigkeit auf jedem Einzelbild in der Bildsequenz, wobei eine erste Schätzung der Momentangeschwindigkeit für jeden Bezugspunkt auf der Grenzlinie bestimmt wird, indem der Verschiebevektor der einzelnen Referenzpunkte von einem ersten Bild zu einem nachfolgenden Bild aus der Bildsequenz durch das zwischen dem ersten Bild und dem nachfolgenden Bild verstrichene Zeitintervall dividiert wird; und wobei das Verfahren weiterhin **gekennzeichnet**

ist durch:

- Bestimmung der Komponenten des Geschwindigkeitsvektors zu jedem Einzelbild der Bildsequenz für alle Referenzpunkte auf der Grenzlinie, indem eine zusätzliche Richtung für die transmurale Schnitte auf dem bereits versetzten Punkt ausgewählt wird und die Geschwindigkeit entlang dieser zusätzlichen Richtung **durch** Anwendung des beschriebenen Verfahrens der sogenannten transmurale Schnitte entlang der genannten zusätzlichen Richtung bestimmt wird, um auf diese Weise den vollständigen Geschwindigkeitsvektor zu ermitteln; die Bestimmung der einzelnen Komponenten des Geschwindigkeitsvektors in jeder Richtung, also insgesamt zwei Komponenten für zweidimensionale Bilder und drei für dreidimensionale Bilder, erfolgt mithilfe der folgenden Schritte:

aa) für jeden Referenzpunkt eines Einzelbildes aus der Bildsequenz wird ein transmurale Schnitt beurteilt, der **durch** eine Linie gebildet ist, die den nachverfolgten Punkt quert und die in Richtung der zusätzlichen Komponente des Geschwindigkeitsvektors ausgerichtet ist, also orthogonal zur Richtung der anderen Komponenten des Geschwindigkeitsvektors;

bb) die entlang jeder transmurale Schnittlinie in jedem Einzelbild der Bildsequenz erfassten Bildpunkte werden für alle Zeitpunkte zugleich in Spalten einer zweidimensionalen Raum-Zeit-Koordinaten-Abbildung platziert;

cc) die Auswertung der Geschwindigkeitskomponente entlang der gewählten Richtung erfolgt anhand der Raum-Zeit-Koordinaten-Abbildung mithilfe eines Kreuzkorrelationsverfahrens der Bildpunktspalte in der Raum-Zeit-Koordinaten-Abbildung; die Geschwindigkeitskomponente ergibt sich dabei als Verhältnis der spaltenweisen Versetzung der Maximalkorrelation zum Zeitintervall zwischen den zugehörigen Einzelbildern.

2. Verfahren nach Anspruch 1, **dadurch gekennzeichnet, dass** es auf geschlossene Grenzlinien angewendet wird.
3. Verfahren nach einem bzw. mehreren der obigen Ansprüche in Verbindung mit abgebildeten Objekten, die wenigstens einen oder mehrere repräsentative Bezugspunkt(e) besitzen, insbesondere einen Ausgangs- und einen Endpunkt einer Grenze, welcher eine Bedeutung als besonderer Bezugspunkt bei der von der Grenzlinie des Objekts ausgeführte Bewegung besitzt,

dadurch gekennzeichnet, dass vor der Durchführung der Nachverfolgung aller Bezugspunkte, die auf der Grenzlinie definiert sind, welche auf dem ersten Einzelbild der Sequenz von mindestens zwei Einzelbildern gezogen ist, ein präventiver Nachverfolgungszyklus der repräsentativen Bezugspunkte gemäß der Verfahren in einem der Ansprüche 1 bzw. 2 oder beide erfolgt.

4. Verfahren nach Anspruch 3, **dadurch gekennzeichnet, dass** die Verfolgung der repräsentativen Bezugspunkte mithilfe des Verfahrens der transmurale Schnitte ausgeführt wird, um Raum-Zeit-Koordinaten-Bilder für die einzelnen repräsentativen Bezugspunkte zu erstellen und die Verschiebung dieser Punkte in jedem Einzelbild aus der Bildsequenz über eine Kreuzkorrelation zwischen jeder der Bildpunktspalten mit der nachfolgenden Bildpunktspalte ermittelt, welche den Bildpunkten entlang des transmurale Schnittes durch denselben repräsentativen Bezugspunkt in den unterschiedlichen Einzelbildern der Bildsequenz entsprechen.
5. Verfahren nach Anspruch 3 oder 4, **dadurch gekennzeichnet, dass** nach dem Ermitteln der Verschiebung der repräsentativen Bezugspunkte auf der Grenzlinie des abgebildeten Objekts in einigen oder sämtlichen Einzelbildern der Bildsequenz die Position und die Verschiebung der übrigen Bezugspunkte auf den Grenzlinien auf jedem Einzelbild der Bildsequenz durch eine Skalierung ursprünglich manuell oder automatisch gezeichneten Grenzlinie im ersten Einzelbild dergestalt, dass sich in jedem Einzelbild, das zu einem folgenden Zeitpunkt gehört, eine zur ursprünglichen Grenzlinie topologisch äquivalente Grenzliniengeometrie ergibt, und dass die repräsentativen Bezugspunkte in allen Einzelbildern der Bildsequenz stets in der richtigen Position gehalten werden, indem die übrigen Bezugspunkte so neu angeordnet werden, dass ein repräsentativer Bezugspunkt die gleiche Korrelation relativ zum Objekt in allen Einzelbildern einer Bildsequenz aufweist.
6. Verfahren nach einem der vorstehenden Ansprüche bzw. mehreren dieser Ansprüche, **gekennzeichnet durch** die folgenden Schritte:
 - a) Erfassung einer Sequenz von mindestens zwei aufeinander folgenden Ultraschall-Einzelbildern von sich bewegendem Gewebe bzw. eines sich bewegendes Objektes, welche Ultraschallbilder in einem bestimmten Zeitintervall aufeinander folgen;
 - b) Auffinden einer Grenzlinie auf einem ersten Einzelbild entweder manuell oder mit Hilfe eines automatischen Algorithmus' zur Grenzbestimmung

mung;

c) Verfolgung der Verschiebungen der Position von einem oder ggf. mehreren repräsentativen Bezugspunkten wenigstens für einige oder für alle Einzelbilder einer Bildsequenz;

d) Skalierung der im ersten Einzelbild gezogenen Grenzlinie für mindestens einige oder für alle folgenden Einzelbilder einer Bildsequenz entsprechend der nachverfolgten Position der repräsentativen Bezugspunkte;

e) Festlegung einer bestimmten Anzahl von weiteren Bezugspunkten, die sich entlang der Grenzlinie im ersten Einzelbild verteilen und auf der Grenzlinie liegen;

f) Nachverfolgung der Position jedes Punktes unabhängig von den anderen in der Bildsequenz;

g) Nachverfolgung der Position der repräsentativen Bezugspunkte und der übrigen Bezugspunkte **dadurch**, dass:

h) für jeden Punkt unabhängig und in jedem Einzelbild der Bildsequenz eine transmurale Schnittlinie festgelegt wird, die aus einer Linie besteht, welche die gezogene Grenzlinie überquert und **durch** den Bezugspunkt verläuft;

i) die entlang jeder transmuralen Schnittlinie in jedem Einzelbild einer Bildsequenz erfassten Bildpunkte werden in Spalten angeordnet, wobei jede der Spalten zu einem Einzelbild der Bildsequenz gehört um eine Momentaufnahme der Entwicklung entlang einer Schnittlinie in einer zweidimensionalen Raum-Zeit-Koordinaten-Abbildung darzustellen;

j) die Verfolgung der Grenzlinie, also der Bildpunktspur entlang jeder transmuralen Schnittlinie, erfolgt entlang der Raum-Zeit-Koordinaten-Abbildung mithilfe eines Verfahrens der Kreuzkorrelation der Bildpunktspalte in der Raum-Zeit-Koordinaten-Abbildung zum ersten Einzelbild mit der Bildpunktspalte der Raum-Zeit-Koordinaten-Abbildung zu einem nachfolgenden Einzelbild der Bildsequenz;

7. Verfahren nach einem vorstehenden Anspruch oder mehreren dieser Ansprüche, **dadurch gekennzeichnet, dass** in Kombination mit Bildern in einer schlechten Qualität, insbesondere mit einem niedrigen Signal-RauschVerhältnis, der Aufbau der Raum-Zeit-Koordinaten-Abbildung mithilfe einer transmuralen Schnittlinie erfolgt, die eine größere Stärke als ein einzelner Bildpunkt aufweist, und dass dann der Durchschnittswert der Stärke ermittelt wird.

8. Verfahren nach einem oder mehreren der vorstehenden Ansprüche, **dadurch gekennzeichnet, dass** es angewandt wird zur Durchführung einer Oberflächengrenzverfolgung bei einer dreidimensionalen Bildgebung und die folgenden Schritte um-

fasst:

l) Erfassung einer Sequenz von dreidimensionalen Ultraschallbild-Bilddatensätzen, wobei jeder dreidimensionale Datensatz in einem vorbestimmten Zeitintervall zum vorhergehenden Datensatz erfasst wird;

m) Festlegung von mindestens einer Hauptschnittebene für jeden dreidimensionalen Datensatz, die entlang einer gewählten Richtung zwecks Erhalt einer Sequenz von zweidimensionalen Einzelbildern entlang der genannten Schnittebene gesetzt wird;

n) manuelles oder automatisches Zeichnen einer Grenzlinie des abgebildeten Objekts auf dem ersten zweidimensionalen Einzelbild der Sequenz von zweidimensionalen Einzelbildern, die entlang der bzw. entlang jeder Hauptschnittebene erfasst worden sind;

o) Durchführen der obigen Nachverfolgungsschritte c) bis j) für jede Sequenz zweidimensionaler Einzelbilder für jede Hauptschnittebene;

p) Festlegen einer bestimmten Anzahl von weiteren sekundären Schnittebenen für jeden dreidimensionalen Datensatz aus der Sequenz von dreidimensionalen Datensätzen, wobei die sekundären Schnittebenen wenigstens eine, vorzugsweise alle Hauptschnittebene(n) kreuzen, wobei die sekundären Schnittebenen voneinander beabstandet in einer vorgegebenen Richtung angeordnet sind, und wobei die sekundären Schnittebenen das durch den jeweiligen dreidimensionalen Datensatz aus der Sequenz von dreidimensionalen Datensätzen dargestellte Objekt in Scheiben unterteilen;

q) für jede sekundäre Schnittebene in der Sequenz der dreidimensionalen Datensätze wird die entsprechende Sequenz von zweidimensionalen Einzelbildern relativ zur sekundären Schnittebene aufgebaut;

r) für jede Sequenz zweidimensionaler Einzelbilder relativ zu jeder sekundären Schnittebene wird eine vermutete Grenzlinie in einem einzelnen Einzelbild festgelegt, indem man die vermutete Grenzlinie über die Schnittpunkte der entsprechenden sekundären Schnittebenen mit der auf der Hauptschnittebene oder den Hauptschnittebenen gezogenen Grenzlinie hinaus ragen lässt.

s) Nachverfolgung der genannten vermuteten Grenzlinie durch Ermitteln einer neuen Grenze durch Anwendung der Verfahrensschritte c) bis j) oder e) bis j), wobei in den genannten Schritten die Zeitkoordinate durch die Raumkoordinate entlang der vermuteten Grenzlinie ersetzt wird, indem:

t) Festlegen einer bestimmte Anzahl von transmuralen Schnitten auf dem einzelnen Einzelbild

aus der Bildsequenz, entsprechend zu jeder sekundären Schnittebene entlang der vermuteten Grenzlinie;

u) Identifikation der Bildpunkte entlang der genannten transmuralen Schnitte und Platzierung der Bildpunkte Seite an Seite entlang jedes transmuralen Schnittes zum Aufbau einer zweidimensionalen Abbildung platziert, bei der die horizontale Achse die räumliche Koordinate entlang der vermuteten Grenzlinie angibt;

v) Durchführung der Kreuzkorrelation zwischen allen aufeinander folgenden Bildpunktspalten in der zweidimensionalen Abbildung und **dadurch** Nachverfolgung der Grenzlinie in einem Einzelbild für jede der Sequenzen zweidimensionaler Einzelbilder, die jeweils einer sekundären Schnittebene entsprechen.

9. Verfahren nach Anspruch 8, **dadurch gekennzeichnet, dass** eine weitere Hauptschnittebene festgelegt werden kann oder mehrere weitere Hauptschnittebenen festgelegt werden können, entlang der bzw. entlang denen wobei für jede weitere Schnittebene die Verfahrensschritte l) bis o) durchgeführt werden.
10. Verfahren nach Anspruch 8 oder Anspruch 9, **dadurch gekennzeichnet, dass** zwei orthogonal Hauptschnittebenen zur Durchführung der oben beschriebenen Verfahrensschritte ausgewählt werden, wobei die Schnittlinie der beiden Hauptschnittebenen eine bevorzugte Richtung der Ebenen festlegt.
11. Verfahren nach einem oder mehrerer der vorstehenden Ansprüche 8 bis 10, **dadurch gekennzeichnet, dass** zur besseren Eingrenzung der Gruppe der sekundären Schnittebenen, welche die Hauptschnittebenen schneiden, die folgenden Schritte vorgesehen sind: Festlegung von Grenzen oder Begrenzungen für einen Distanzbereich, innerhalb derer die Gruppe der sekundären Schnittebenen festzulegen ist.
12. Verfahren nach Anspruch 11, **dadurch gekennzeichnet, dass** eine Richtung, die der Verteilung der sekundären Schnittebenen entspricht, ausgewählt wird, welche die gleiche Richtung wie zur Bestimmung der Hauptschnittebenen darstellt, entlang welcher Richtung Grenzen bestimmt werden für eine Abstandsverteilung, innerhalb derer die Gruppe der sekundären Schnittebenen festgelegt sind, und wobei die sekundären Schnittebenen mindestens transversal und insbesondere senkrecht zu der Richtung sind.
13. Verfahren nach einem oder mehreren der vorste-

henden Ansprüche, **dadurch gekennzeichnet, dass** die Korrekte Grenzlinie überlagert auf dem entsprechenden angezeigten Einzelbild als eine hervorgehobene Linie in einer Farbe angezeigt wird, die sich vom angezeigten Graustufen-B-Modus-Bild abhebt.

Revendications

1. Procédé pour suivre la position et la vitesse de contours d'objets dans des images d'échographie à deux ou trois dimensions, comprenant les étapes suivantes:

acquérir une séquence d'au moins deux trames d'image à ultrasons consécutives d'un tissu mobile ou d'un objet mobile, lesdites trames d'image à ultrasons sont séparées dans le temps par un certain intervalle de temps;

définir automatiquement ou manuellement un certain nombre de points de référence d'un contour d'un tissu ou objet mobile au moins sur une première trame d'image de la séquence de trames d'image acquises;

suivre automatiquement le contour du tissu ou objet mobile dans la au moins une autre trame suivante en déterminant la nouvelle position des points de référence du contour dans au moins une trame d'image suivante de la séquence de trames d'image en estimant la position desdits points de référence dans ladite au moins une trame d'image suivante de la séquence de trames d'image sur la base des données d'image à ultrasons de la séquence acquise des trames d'image;

la séquence de trames d'image acquise est une séquence d'images à ultrasons consécutive de mode B, de l'échelle de gris;

sur une première trame, une ligne de contour est tracée soit manuellement soit par un algorithme de détection de contour automatique, le contour étant défini par une trace de pixels de la trame d'image coïncidant avec ladite ligne de contour;

la trace initiale de pixels coïncidant avec la ligne de contour tracée manuellement ou automatiquement est suivie dans le temps, c'est-à-dire dans la au moins une trame d'image suivante en recherchant la probabilité maximale de la trace de pixels dans la trame d'image suivante, avec la trace de pixels dans la première trame d'image ou trame d'image précédente dans le temps de la séquence de trames d'image en analysant les pixels d'image au voisinage de ladite trace de pixels;

la poursuite de la ligne de contour est exécutée en définissant un certain nombre de points de

référence sur la ligne de contour tracée manuellement ou automatiquement sur la première trame d'image et en utilisant le procédé des soi-disant coupes transmursales;

lesdites coupes transmursales consistent en définissant pour chaque point de référence une ligne qui se croise avec la ligne de contour tracée sur une première trame d'image, et chacune des lignes passant à travers un point de référence; chaque ligne de coupe transmurale ayant une direction définie qui peut être d'une manière typique la direction orthogonale à la ligne de contour au point de référence;

exécuter l'étape mentionnée ci-dessus de la définition de coupes transmursales pour chaque trame d'image de la séquence de trames et pour chaque point de référence sélectionné;

les pixels pris le long de chaque ligne transmurale dans chacune des trames d'image de la séquence de trames d'image étant ensuite placés en colonne, chaque colonne correspondant à une trame de la séquence d'images, formant une représentation bidimensionnelle espace-temps de l'évolution de la position de chaque point de référence le long de la coupe transmurale correspondante;

la poursuite de la ligne de contour, c'est-à-dire de la trace de pixels, est exécutée pour chaque point de référence défini sur ladite ligne de contour le long de l'image correspondante bidimensionnelle espace-temps en utilisant une procédure de corrélation croisée de la colonne de pixels dans l'image espace-temps correspondant à une première trame d'image avec la colonne de pixels dans l'image espace-temps correspondant à une trame d'image successive de la séquence de trames d'image;

comprenant des étapes pour déterminer la vitesse instantanée de la ligne de contour sur chaque trame d'image de la séquence de trames d'image, moyennant quoi une première estimation de la vitesse instantanée est déterminée pour chaque point de référence sur la ligne de contour en divisant le vecteur de déplacement de chacun des points de référence d'une première trame d'image à une trame d'image suivante de la séquence de trames d'image par l'intervalle de temps qui s'est produit entre ladite première trame d'image et ladite trame d'image suivante,

et ledit procédé est **caractérisé en outre par** les étapes de

déterminer les composantes du vecteur de vitesse sur chacune des trames d'image de la séquence de trames d'image pour chacun des points de référence sur la ligne de contour en sélectionnant une direction additionnelle pour les coupes transmursales sur le point déjà dépla-

cé et en évaluant la vitesse dans la direction additionnelle en appliquant lesdites étapes de procédé des soi-disant coupes transmursales dans ladite direction additionnelle requise pour évaluer le vecteur de vitesse complet;

l'évaluation de chacune de la ou des composante(s) du vecteur de vitesse dans chaque direction, le nombre total de composantes étant de deux pour l'imagerie à deux dimensions et de trois pour l'imagerie à trois dimensions; étant exécutée selon les étapes suivantes:

aa) pour chaque point de référence, sur chaque trame d'image de la séquence de trames d'image, une coupe transmurale consistant en une ligne qui croise le point suivi et dirigée dans la direction dans laquelle la composante additionnelle de la vitesse est évaluée, orthogonale à la direction pour les autres composantes du vecteur de vitesse;

bb) les pixels pris le long de chaque ligne de coupe transmurale dans chacune des trames d'image de la séquence de trames d'image sont placés en colonnes pour tous les instants immédiatement dans une représentation espace-temps bidimensionnelle;

cc) l'évaluation de la composante de vitesse dans la direction sélectionnée est exécutée le long de l'image espace-temps en utilisant une procédure de corrélation croisée de la colonne de pixels dans l'image espace-temps, ladite vitesse étant fournie par le rapport du déplacement par colonne du maximum de corrélation et de l'intervalle de temps entre les trames correspondantes.

2. Procédé selon la revendication 1, **caractérisé en ce qu'il** est appliqué à des lignes de contour fermées.
 3. Procédé selon l'une ou plusieurs des revendications précédentes en combinaison avec des objets imagés ayant au moins un ou plusieurs points de référence représentatifs, en particulier un point de début et un point de fin d'un contour qui ont une pertinence en tant que points de référence particuliers dans le mouvement exécuté par la ligne de contour de l'objet,
- caractérisé en ce qu'avant** l'exécution de la poursuite de tous les points de référence définis sur la ligne de contour tracée sur une première trame d'image de la séquence d'au moins deux trames d'image, un cycle de poursuite préventif seulement des points de référence représentatifs est exécuté selon le procédé selon l'une ou plusieurs des revendications 1 à 2.

4. Procédé selon la revendication 3, **caractérisé en ce que** la poursuite des points de référence représentatifs est exécutée en utilisant le procédé des coupes transmursales pour construire des images espace-temps de chacun des points de référence représentatifs et pour déterminer le déplacement de ces points dans chacune des trames de la séquence de trames d'image par une corrélation croisée entre chacune des colonnes de pixels avec la colonne de pixels successive correspondant aux pixels le long de la coupe transmurale sur le même point de référence représentatif dans les trames d'image différentes de la séquence de trames d'image.
5. Procédé selon la revendication 3 ou 4, **caractérisé en ce que** après avoir déterminé le déplacement des points de référence représentatifs sur la ligne de contour de l'objet imagé dans quelques-unes ou toutes les trames de la séquence de trames d'image, la position et le déplacement des autres points de référence sur les lignes de contour à chaque trame d'image de la séquence de trames d'images sont obtenus en remettant à l'échelle la ligne de contour initiale tracée manuellement ou automatiquement dans la première trame d'image de manière à obtenir dans chaque trame d'image correspondant à un instant successif une géométrie de ligne de contour topologiquement équivalente par rapport à la ligne de contour initiale et pour maintenir les points de référence représentatifs toujours dans la position correcte dans toutes les trames de la séquence de trames d'image en réagénçant les autres points de référence de telle sorte que les points de référence représentatifs conservent la même signification relativement à l'objet dans toutes les trames de la séquence de trames d'image.
6. Procédé selon l'une ou plusieurs des revendications précédentes, **caractérisé par** les étapes suivantes:
- a) acquérir une séquence d'au moins deux trames d'image à ultrasons consécutives d'un tissu mobile ou d'un objet mobile, lesdites trames d'image à ultrasons sont séparées dans le temps par un certain intervalle de temps;
 - b) suivre une ligne de contour sur une seule première trame soit manuellement soit à l'aide d'un algorithme de traçage de contour automatique;
 - c) suivre les déplacements de position d'un ou de plusieurs points de référence représentatifs éventuellement présents sur toute la séquence de trames d'image consécutives;
 - d) remettre à l'échelle la ligne de contour tracée sur la première trame d'image au moins pour quelques-unes ou pour chacune des trames d'image suivantes de la séquence de trames d'image selon la position correspondante suivie des points de référence représentatifs;
 - e) définir un certain nombre d'autres points de référence distribués le long de la ligne de contour sur la première trame d'image et tombant sur ladite ligne de contour;
 - f) suivre la position de chaque point indépendamment des autres le long de la séquence de trames d'images;
 - g) la poursuite de la position des points de référence représentatifs et des autres points de référence étant exécutée par
 - h) pour chaque point indépendamment et dans chacune des trames d'image de la séquence de trames d'image définissant une ligne de coupe transmurale consistant en une ligne qui croise la ligne de contour tracée et passant à travers ledit point de référence;
 - i) les pixels pris le long de chaque ligne de coupe transmurale dans chacune des trames d'image de la séquence de trames d'image sont placés en colonnes, chaque colonne correspondant à une trame de la séquence d'images pour représenter l'évolution le long d'une ligne de coupe transmurale, pour tous les instants immédiatement dans une représentation espace-temps bidimensionnelle;
 - j) la poursuite du contour, c'est-à-dire de la trace de pixels le long de chaque ligne de coupe transmurale est exécutée le long de l'image espace-temps en utilisant une procédure de corrélation croisée de la colonne de pixels dans l'image espace-temps correspondant à une première trame d'image, la colonne de pixels dans l'image espace-temps correspondant à une trame d'image successive de la séquence de trames d'image.
7. Procédé selon l'une ou plusieurs des revendications précédentes, **caractérisé en ce que**, en combinaison d'images d'une qualité médiocre, c'est-à-dire avec un rapport de signal-à-bruit bas, la représentation espace-temps le long des coupes transmursales est formée en utilisant une ligne pour la coupe transmurale d'une épaisseur plus grande que celle d'un seul pixel et par extraction de la valeur moyenne sur une telle épaisseur.
8. Procédé selon l'une ou plusieurs des revendications précédentes, **caractérisé en ce qu'il** est appliqué pour exécuter une poursuite de contour de surface dans l'imagerie tridimensionnelle, et comprenant les étapes suivantes:
- l) acquérir une séquence d'ensembles de données d'imagerie à ultrasons tridimensionnels, chaque ensemble de données tridimensionnel étant acquis avec un intervalle de temps prédéterminé de celui qui précède;
 - m) définir au moins un plan de section principale

de chaque ensemble de données tridimensionnel le long d'une direction sélectionnée pour obtenir une séquence de deux trames d'image dimensionnelles le long dudit plan de section;

n) tracer une ligne de contour de l'objet image soit manuellement soit automatiquement sur les premiers deux trames d'image dimensionnelles de la séquence des deux trames d'image dimensionnelles prises le long dudit plan de section principal ou chacun desdits plans de section principaux;

o) exécuter pour les étapes de poursuite c) à j) divulguées préalablement pour chaque séquence de trames d'image bidimensionnelles pour chaque plan de section principal correspondant;

p) pour chaque ensemble de données tridimensionnelles de la séquence d'ensembles de données tridimensionnelles définissant un nombre pré-établi d'autres plans de section secondaires croisant le au moins un, de préférence tous les plans de section principaux, lesdits plans de section secondaires étant espacés les uns des autres le long d'une direction prédéterminée et divisant l'objet représenté par chaque ensemble de données tridimensionnelles de la séquence d'ensembles de données tridimensionnelles en tranches;

q) pour chaque plan de section secondaire dans la séquence des ensembles de données tridimensionnelles formant la séquence correspondante des trames d'image bidimensionnelles relativement audit plan de section secondaire;

r) pour chaque séquence de trames d'image bidimensionnelles relativement à chaque plan de section secondaire déterminant une ligne de contour de supposition dans une seule trame, en amenant la ligne de contour de supposition à passer sur les points d'intersection du plan de section secondaire correspondant, la ligne de contour étant tracée sur le plan de section principal ou des plans de section principaux;

s) suivre ladite ligne de contour de supposition en détectant un nouveau contour en appliquant les étapes de procédé selon c) à j) ou e) à j) en substituant la coordonnée de temps dans lesdites étapes divulguées par la coordonnée spatiale le long de ladite ligne de contour de supposition en

t) définir un certain nombre de coupes transmurales sur la trame d'image unique de la séquence de trames d'image correspondant à chaque plan de section secondaire le long de la ligne de contour de supposition;

u) identifier les pixels le long desdites coupes transmurales et placer les pixels le long de toutes les coupes transmurales côte à côte pour former une image bidimensionnelle, où l'axe horizontal indique la coordonnée spatiale le long

de la ligne de contour de supposition;

v) exécuter la corrélation croisée entre chacune des colonnes de pixels consécutives dans ladite image bidimensionnelle et suivre ainsi la ligne de contour dans une trame pour chacune des séquences de trames d'image bidimensionnelles correspondant à chacun des plans de section secondaires.

9. Procédé selon la revendication 8, **caractérisé en ce qu'un** ou plusieurs autres plans de section principaux peuvent être définis, le long de chacun des autres plans en section, les étapes de procédé 1) à o) sont exécutées.
10. Procédé selon les revendications 8 ou 9, **caractérisé en ce que** deux plans de section principaux orthogonaux sont sélectionnés pour exécuter les étapes de procédé mentionnées ci-dessus, la ligne de croisement des deux plans de section principaux définissant une direction préférée desdits plans.
11. Procédé selon l'une ou plusieurs des revendications précédentes 8 à 10, **caractérisé en ce que** pour mieux définir le groupe de plans de section secondaires coupant les plans de section principaux, les étapes suivantes sont exécutées: définir des liaisons ou des limites pour une plage de distances dans laquelle le groupe desdits plans de section secondaires doit être défini.
12. Procédé selon la revendication 11, **caractérisé en ce qu'une** direction dans laquelle les plans de section secondaires sont distribués, est sélectionnée, qui est la même direction définie pour déterminer les plans de section principaux, le long de cette direction des liaisons sont déterminées pour les extrémités d'une plage de distances dans laquelle le groupe de plans de section secondaires est défini, et lesdits plans de section secondaires sont au moins transversaux, particulièrement perpendiculaires à ladite direction.
13. Procédé selon l'une ou plusieurs des revendications précédentes, la ligne de contour correcte suivie est affichée en étant superposée à la trame d'image affichée correspondante comme une ligne soulignée, **caractérisé par** une couleur qui est différente de l'image de mode B à l'échelle de gris affichée.

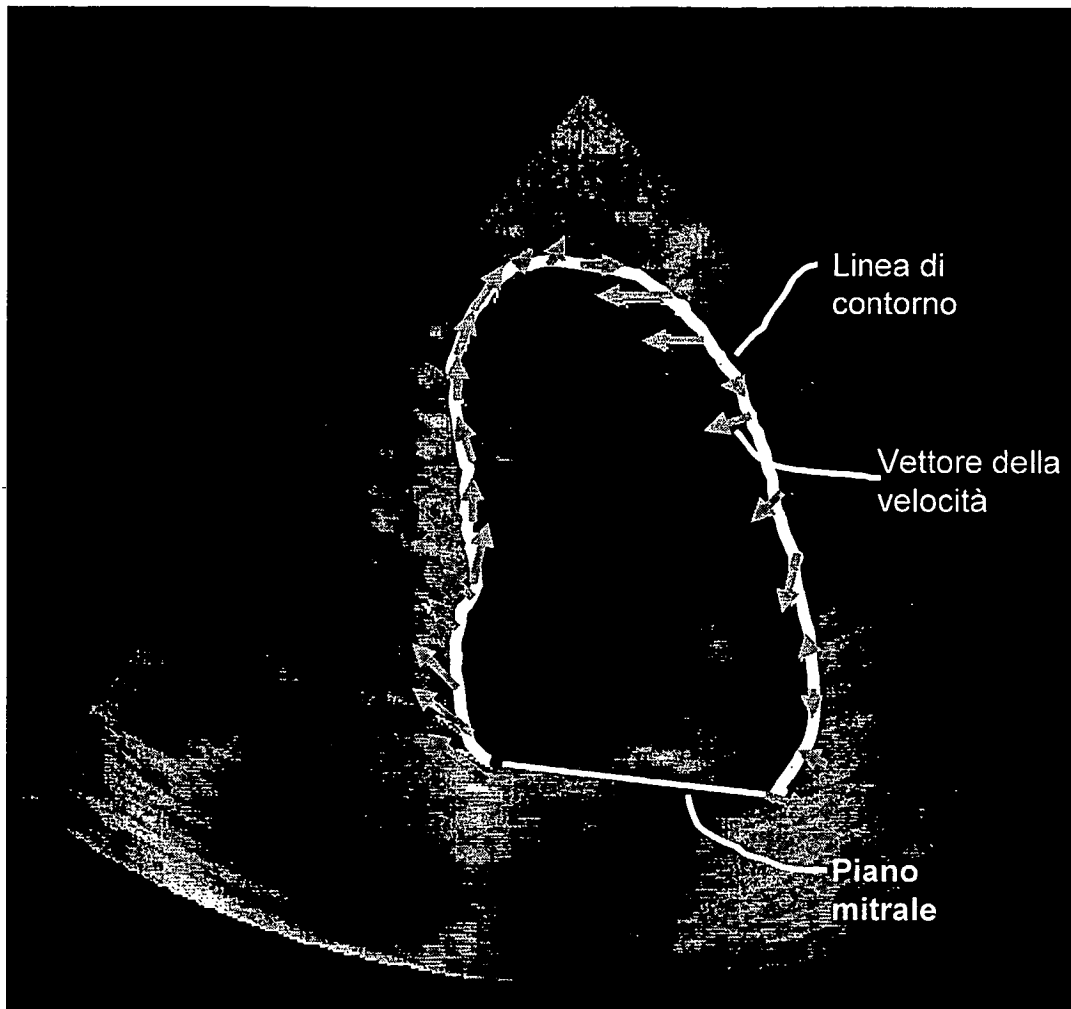


Fig. 1

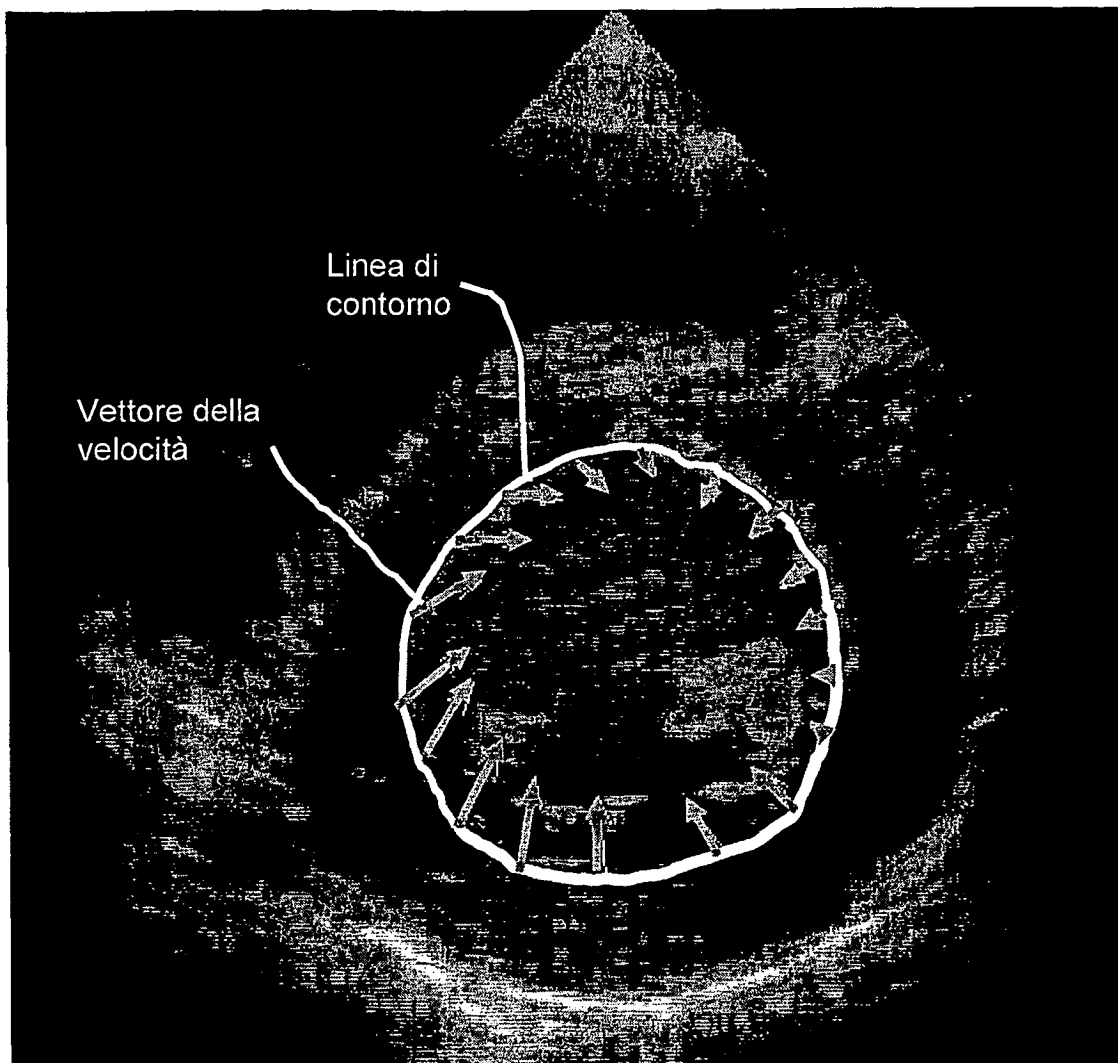


Fig. 2

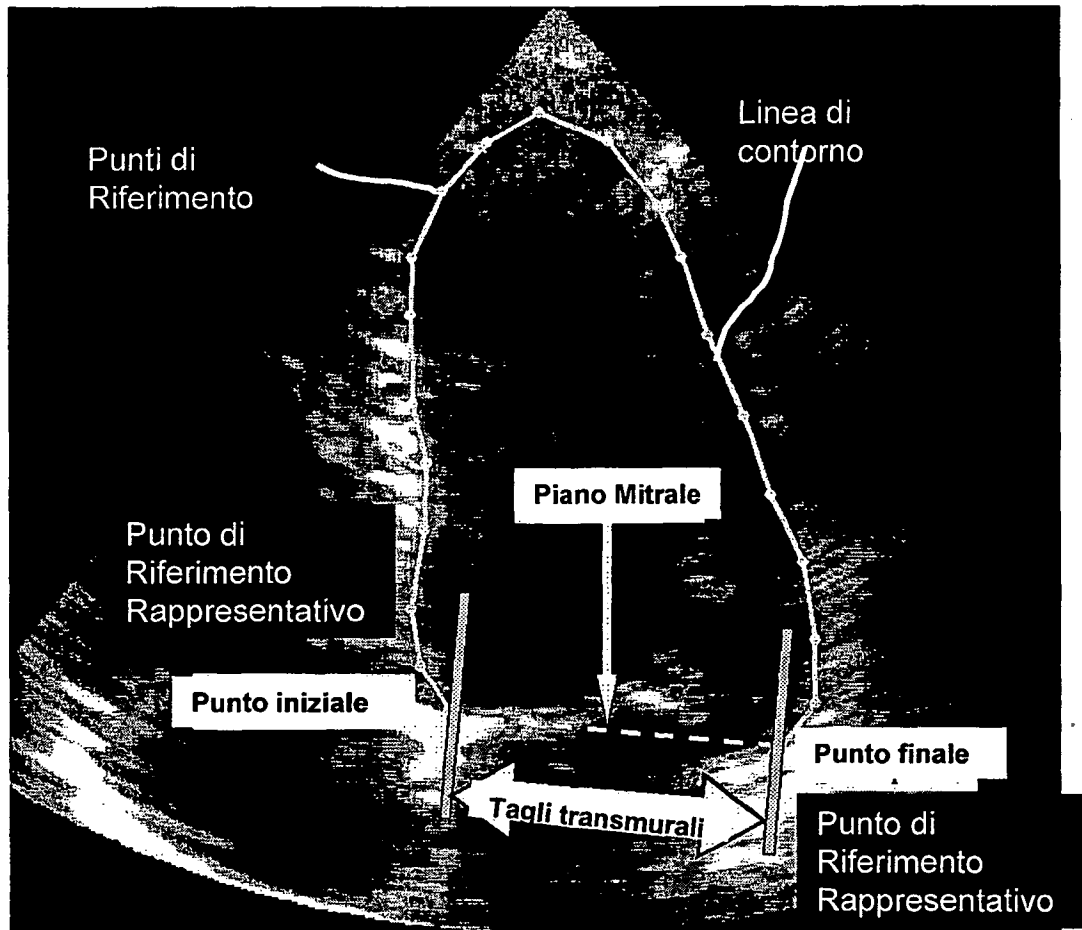


Fig. 3

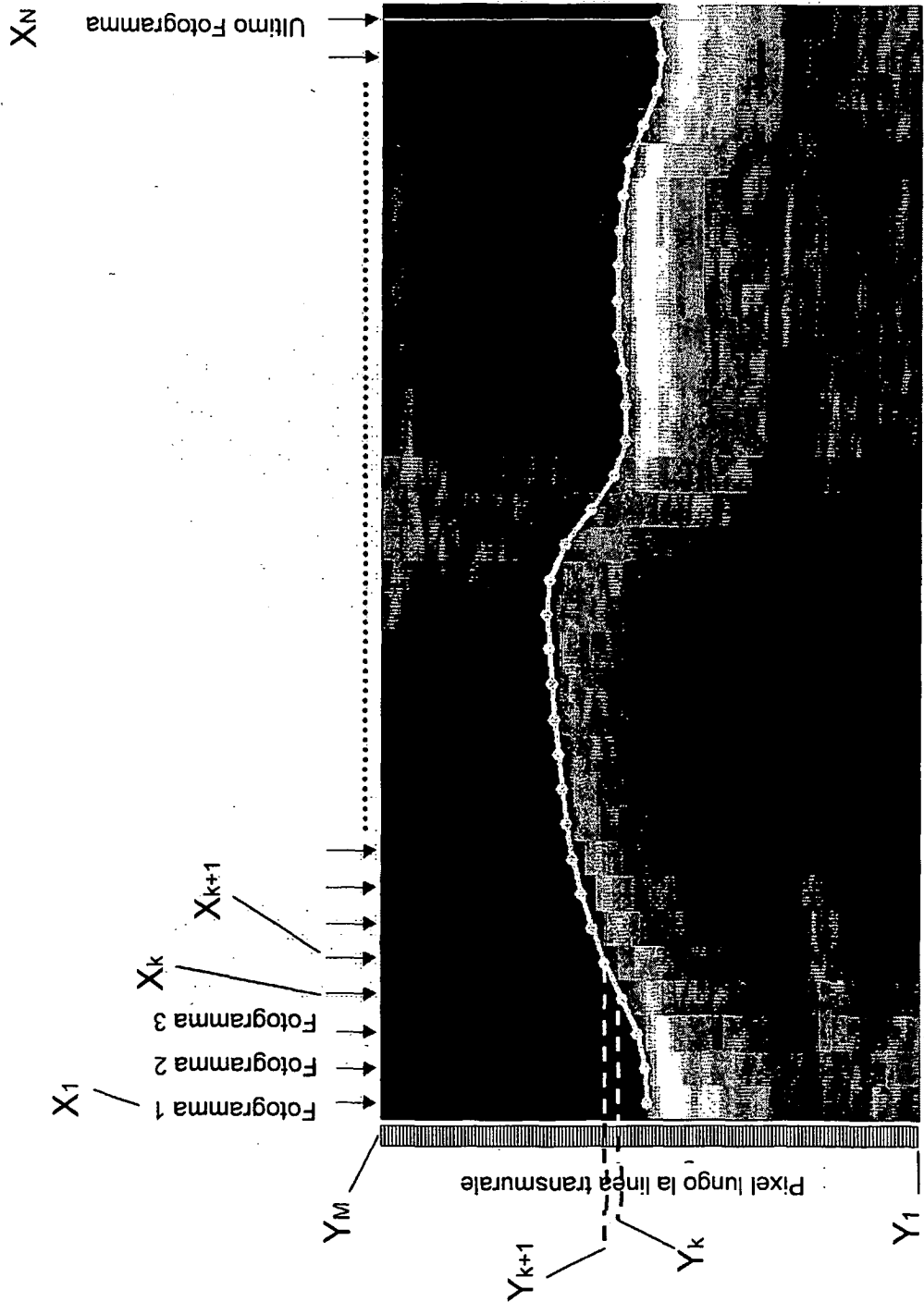


Fig. 4

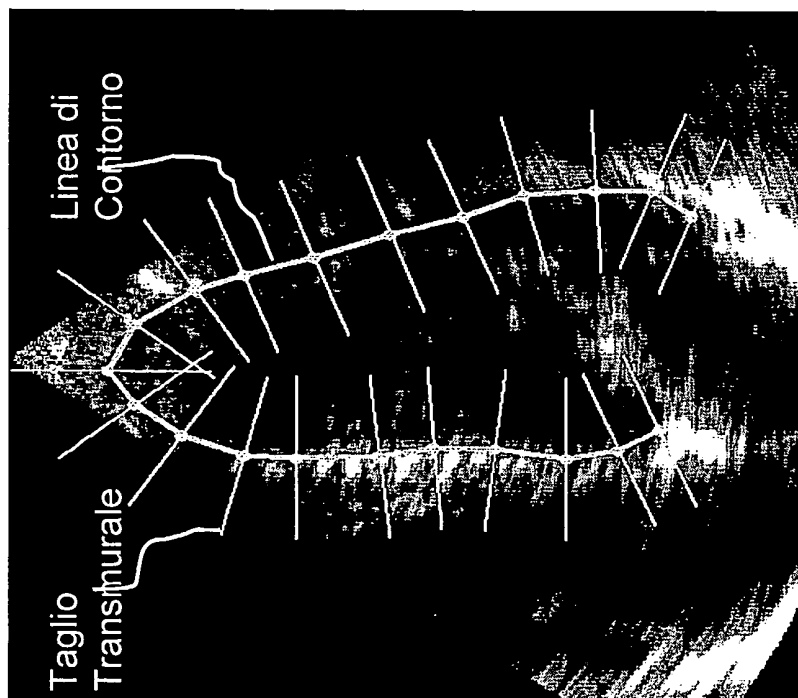
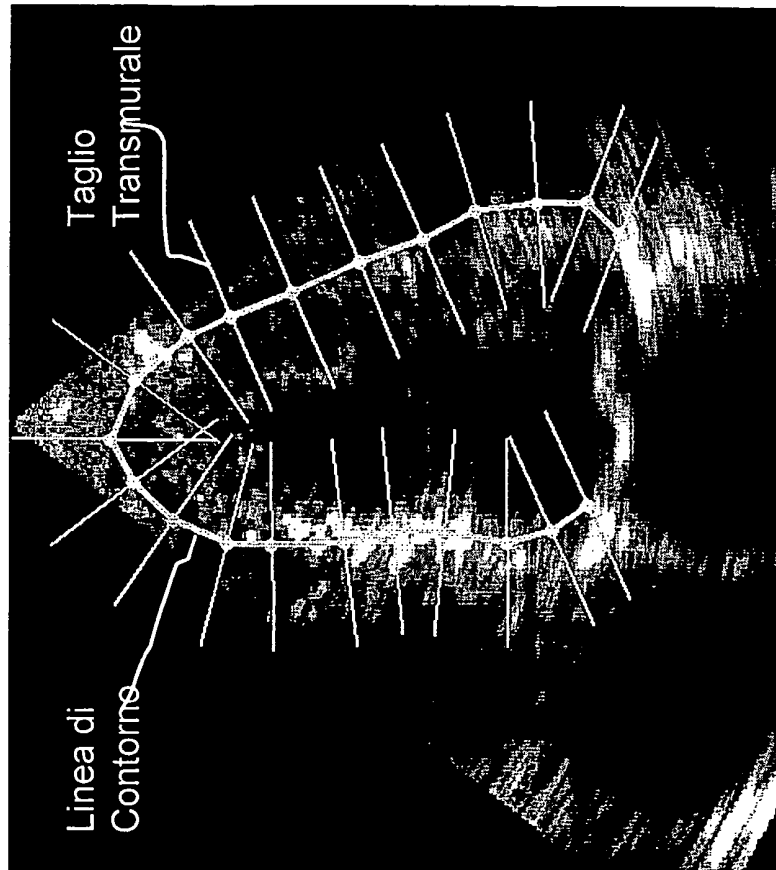


Fig. 5

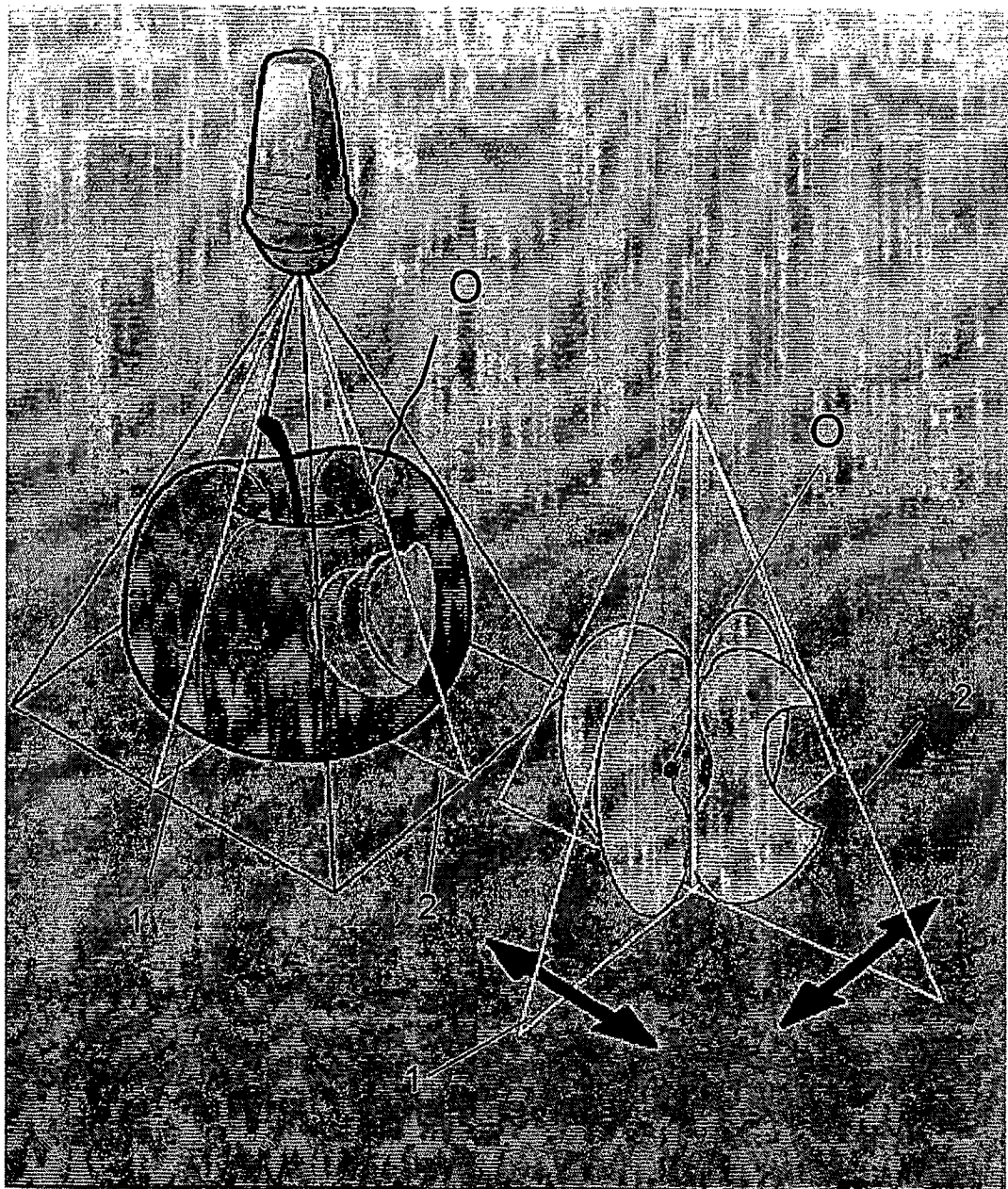


Fig 6

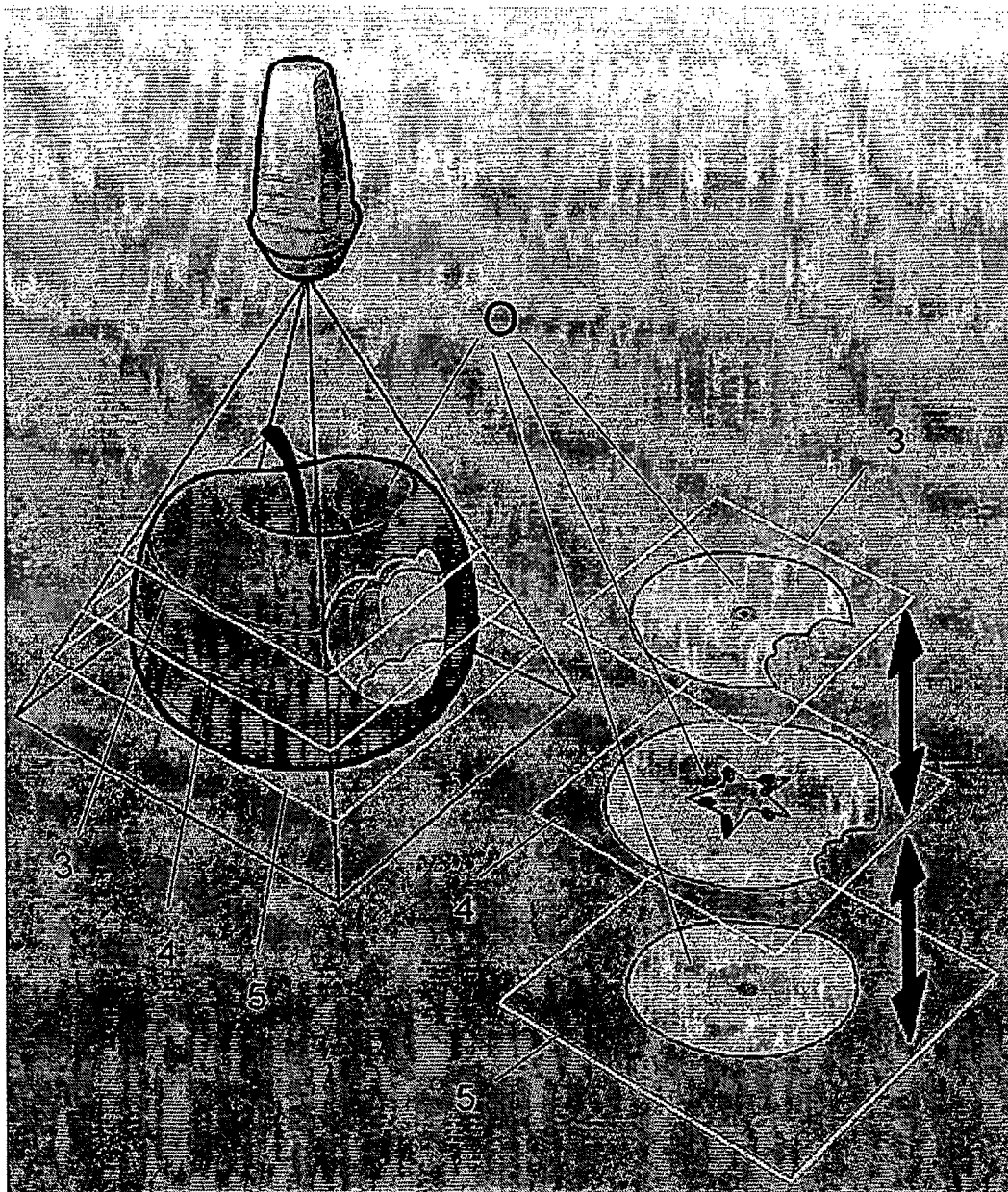


Fig. 7

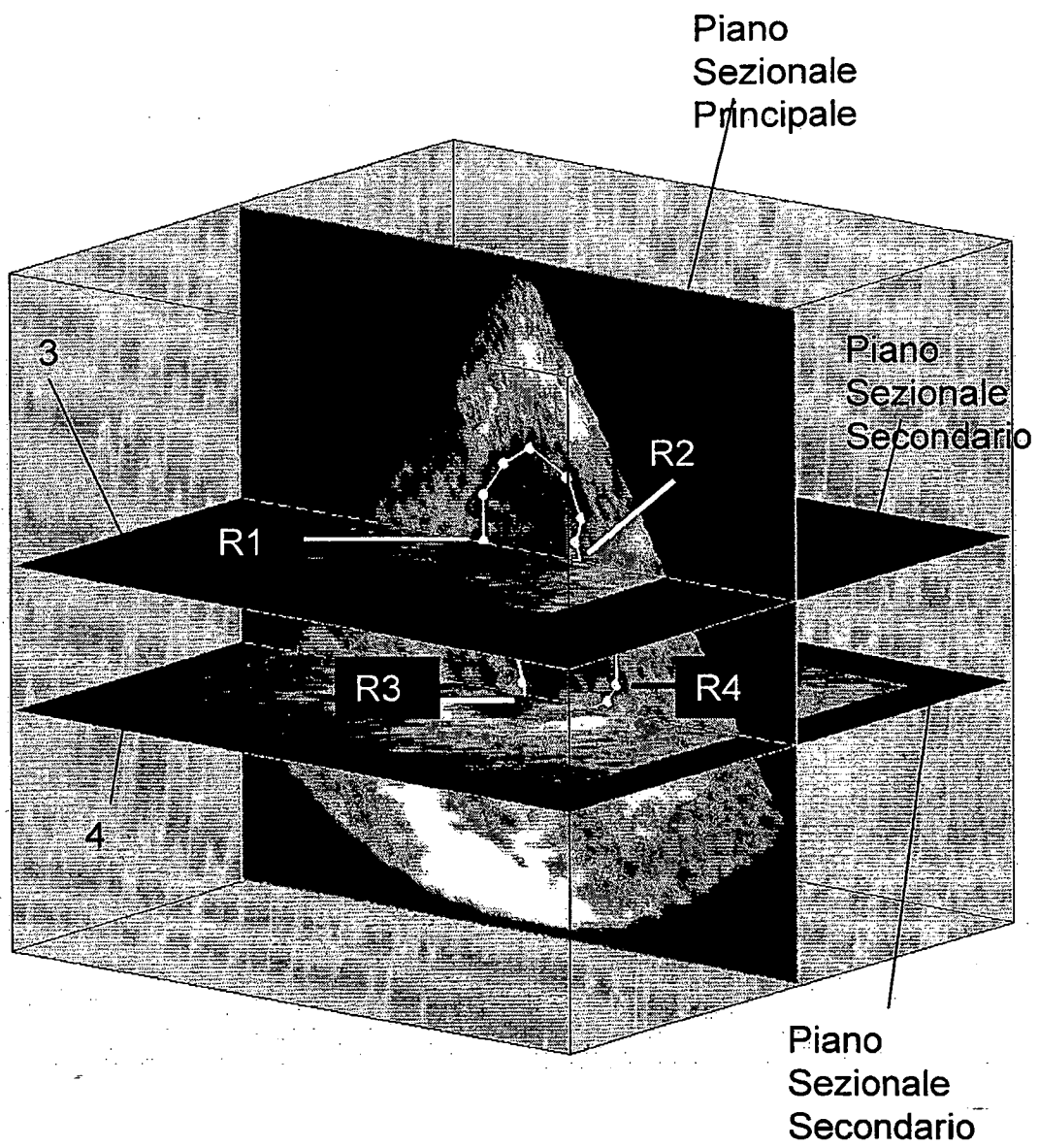


Fig 8

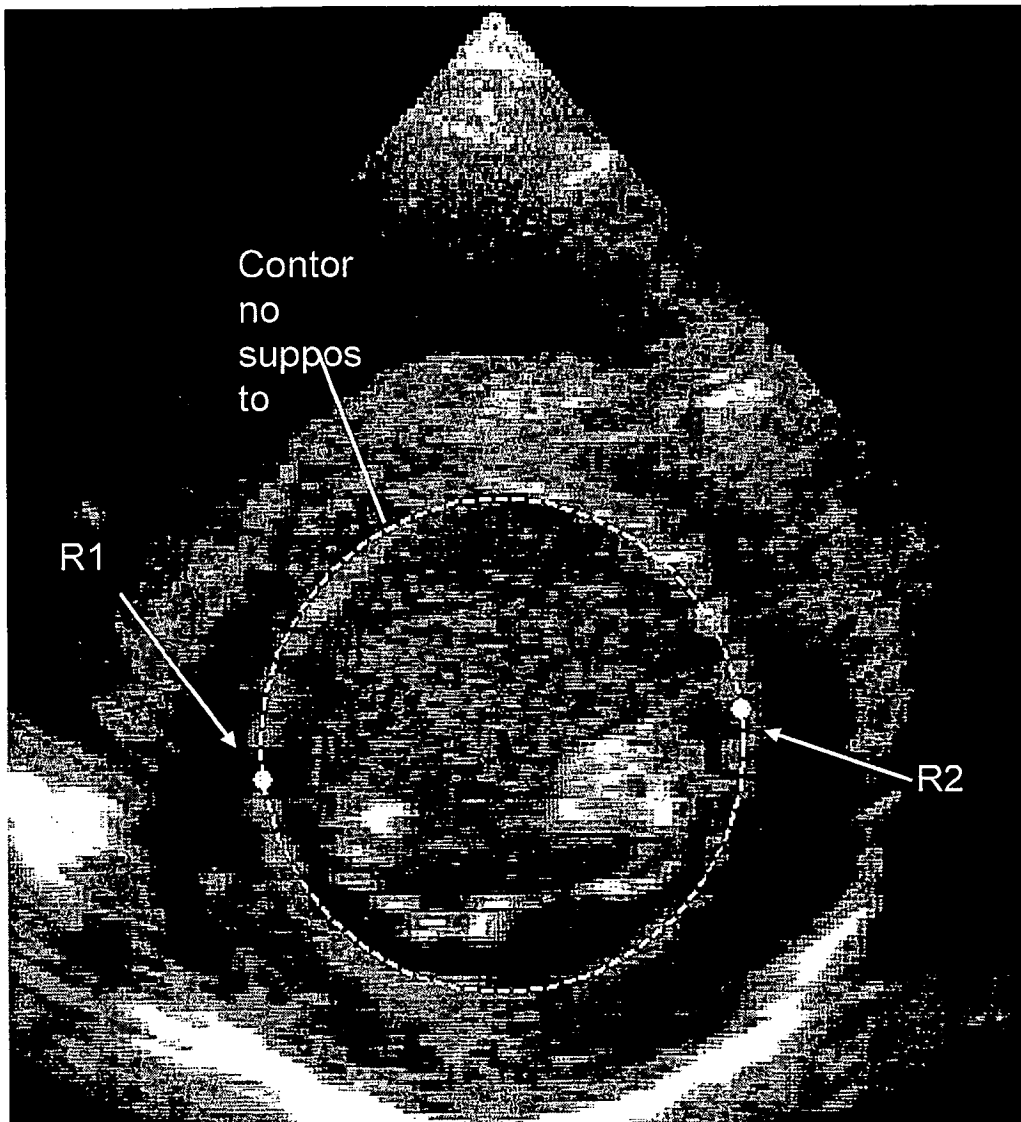


Fig. 9

REFERENCES CITED IN THE DESCRIPTION

This list of references cited by the applicant is for the reader's convenience only. It does not form part of the European patent document. Even though great care has been taken in compiling the references, errors or omissions cannot be excluded and the EPO disclaims all liability in this regard.

Patent documents cited in the description

- WO 0245587 A [0005]
- WO 2003071950 A [0008]
- IT 0200114 W [0041]

专利名称(译)	一种在二维或三维数字回波描记图像中跟踪物体边界位置和速度的方法		
公开(公告)号	EP1522875B1	公开(公告)日	2012-03-21
申请号	EP2003425639	申请日	2003-09-30
[标]申请(专利权)人(译)	百胜集团		
申请(专利权)人(译)	ESAOTE S.P.A. AMID S.R.L.		
当前申请(专利权)人(译)	BRACCO成像S.P.A ESAOTE S.P.A.		
[标]发明人	PEDRIZZETTI GIANNI TONTI GIOVANNI		
发明人	PEDRIZZETTI, GIANNI TONTI, GIOVANNI		
IPC分类号	G01S15/89 A61B8/08 G01S7/52 G06T5/00 G06T7/20		
CPC分类号	A61B8/0883 A61B8/08 A61B8/0891 A61B8/485 A61B8/486 G01S7/52036 G01S7/52046 G01S7/52063 G01S7/52069 G01S15/8981 G01S15/8993 G06T7/0012 G06T7/12 G06T7/251 G06T2207/10016 G06T2207/10132 G06T2207/30048		
其他公开文献	EP1522875A1		
外部链接	Espacenet		

摘要(译)

一种在二维或三维数字图像中跟踪物体边界的位置和速度的方法，特别是在回波描记图像中，包括以下步骤：获取移动组织或移动物体的至少两个连续超声图像帧的序列。及时隔开一定的时间间隔；至少在所获取的图像帧序列的第一图像帧上自动或手动地定义移动的组织或对象的边界的特定数量的参考点；通过估计所述图像帧序列的至少一个后续图像帧中的边界的参考点的新位置，自动跟踪所述至少一个后续帧中的移动组织或对象的边界。基于所获取的图像帧序列的超声图像数据，在所述图像帧序列的所述至少后续图像帧中的参考点。在本发明中，所获取的图像帧序列是一系列连续的B模式灰度超声图像；在第一帧上，手动或通过自动边界检测算法绘制边界线。手动或自动绘制的边界线的原始像素轨迹随着时间的推移，即在至少一个后续图像帧中，通过在第一个或第一个像素的轨迹中搜索下一个图像帧中的像素轨迹的最大似然性。通过分析所述像素轨迹附近的图像像素，及时地预先显示图像帧。

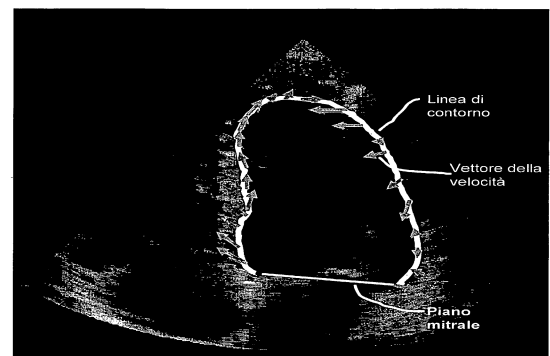


Fig. 1