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(54) **3D TRACKING OF AN INTERVENTIONAL INSTRUMENT IN 2D ULTRASOUND GUIDED INTERVENTIONS**

3D-VERFOLGUNG EINES INTERVENTIONELLEN INSTRUMENTS BEI 2D-ULTRASCHALLGESTEUERTEN EINGRIFFEN

SUIVI 3D D'UN INSTRUMENT D'INTERVENTION DANS DES INTERVENTIONS GUIDÉES PAR ULTRASONS 2D

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(73) Proprietor: **Koninklijke Philips N.V.**
5656 AG Eindhoven (NL)

(72) Inventors:
• **BHARAT, Shyam**
5656 AE Eindhoven (NL)

• **JAIN, Ameet Kumar**
5656 AE Eindhoven (NL)
• **BONILLAS VACA, Antonio**
5656 AE Eindhoven (NL)

(74) Representative: **Fairley, Peter Douglas**
Philips Intellectual Property & Standards
High Tech Campus 5
5656 AE Eindhoven (NL)

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Description

FIELD

[0001] The following relates generally to the medical arts, ultrasound-guided interventional procedure arts, prostate biopsy arts, and the like.

BACKGROUND

[0002] Ultrasound-guided interventional procedures, such as biopsies, brachytherapy seed implantation, cryoablation, laser ablation, or so forth, utilize ultrasound imaging to guide the interventional instrument to the target tissue. For example, in a transperineal prostate intervention, ultrasound imaging using a transrectal ultrasound (TRUS) probe, typically along with a guidance grid abutted against the perineum, is used to guide the needle insertion. The ultrasound imaging performed during the interventional procedure is usually two-dimensional (2D) imaging. To contextualize the 2D ultrasound images, a pre-acquired three-dimensional (3D)-TRUS ultrasound image and/or a 3D magnetic resonance (MR) image of the target region may be used (Kruecker et al., "Fusion of transrectal ultrasound with pre-acquired MRI for prostate biopsy guidance", MEDICAMUNDI 52/1 2008/07 at pages 25-31 (2008)). However, instrument contrast in ultrasound is usually poor, with intermittent instrument visibility, leading to the so-called "invisible tool" phenomenon.

[0003] To address poor instrument contrast in ultrasound, dedicated ultrasound sensors may be mounted on the interventional instrument (Mung et al., "Tool Tracking for Ultrasound-Guided Interventions", G. Fichtinger, A. Martel, and T. Peters (Eds.): MICCAI 2011, Part I, LNCS 6891, pp. 153-60 (2011)). In one approach, the sensor serves as an active ultrasound transponder by re-radiating received ultrasound pulses. In another approach, the sensor outputs a voltage when the ultrasound signal is received. In either approach, the knowledge of the combination of the direction of the ultrasound beam that sonicates the sensor and the time interval between ultrasound pulse emission and the sensor response ("time of flight") enables localization of the sensor. If this approach is used with real-time 3D-TRUS ultrasound imaging, then localization in the three-dimensional space is achievable.

[0004] A document US 2003/060700 A1 relates to an imaging ultrasound system that is provided with an ultrasound transducer and an image processing unit for the acquisition of a three-dimensional ultrasound image of the body of a patient, as well as with a catheter for carrying out a therapeutic or diagnostic intervention in the body of the patient. The catheter accommodates, in addition to the customary instruments necessary to carry out its task, three ultrasound receivers that are mounted at a distance from one another on the tip of the catheter and are capable of detecting the arrival of scan signals of the

ultrasound transducer. The distance between the ultrasound transducer and the receivers can be calculated from the transit time of the scan signals. The receivers can thus be localized in space; this enables notably the selection of, for example, the plane from the three-dimensional ultrasound data that contains all three receivers of the catheter. The tip of the catheter can thus be automatically tracked and displayed on a monitor at all times without manual displacement of the ultrasound transducer being necessary.

[0005] However, in practice a 2D ultrasound is more commonly employed for live guidance during needle insertion. 2D ultrasound is faster, can be performed using a lower cost ultrasound transducer array, and the 2D image is readily displayed on a video display component of the ultrasound device display. More particularly, in transperineal prostate biopsy procedures, a pre-procedurally acquired 3D MR data set is used to delineate the target from where the biopsy sample will be taken. At the beginning of the biopsy procedure, a 3D-TRUS image set is acquired by scanning the TRUS probe manually from prostate base to apex (or by rotating the probe about an axis parallel to its own, from left lateral to right lateral extremes of the prostate (or vice versa), while imaging in sagittal orientation) and reconstructed from 2D TRUS image frames and the 3D-TRUS is registered to the previously acquired MR data set. Thereafter, the TRUS probe is used to acquire 2D images at the sagittal orientation (for a prostate procedure), for example using conventional brightness or B-mode imaging, to provide live 2D guidance as the biopsy needle is inserted. The TRUS probe is tracked using electromagnetic (EM) or some other TRUS probe spatial tracking technology, and the live 2D ultrasound images are thereby linked to the corresponding frame of the reconstructed 3D TRUS image, and therefore, to the MR data set, from the TRUS-MR registration.

SUMMARY

[0006] In one disclosed aspect, a tracking device is disclosed for tracking an interventional instrument that has one or more ultrasound sensors disposed with the interventional instrument. The tracking device comprises an ultrasound imaging device including an ultrasound probe configured to acquire a two-dimensional (2D) ultrasound image, and an electronic processor. The electronic processor is programmed to operate the ultrasound imaging device to perform an interventional instrument tracking method including: operating the ultrasound imaging device to display a 2D ultrasound image of a visualization plane; performing 2D ultrasound sweeps of a plurality of planes that encompasses the visualization plane and, for each 2D ultrasound plane of the plurality of planes, detecting a signal emitted by each ultrasound sensor in response to the 2D ultrasound sweep of the plane; for each ultrasound sensor, identifying an optimal plane of the plurality of planes for which the detected

signal emitted by the ultrasound sensor is highest and identifying the location of the ultrasound sensor in the optimal plane, and identifying the location of the ultrasound sensor in a three dimensional (3D) reference space based on the location of the ultrasound sensor in the optimal plane and knowledge of how the optimal plane relates to the 3D space (e.g., 3D TRUS/MRI); and determining spatial information for the interventional instrument, including at least one of tip location and orientation of the interventional instrument, based on the identified locations of the one or more ultrasound sensors in the 3D reference space. The location of the ultrasound sensor in the optimal plane may be identified, for example, based on analyzing the sensor signal as a function of the timing of the beams fired by the ultrasound probe.

[0007] One advantage resides in providing three-dimensional interventional instrument information using 2D live ultrasound imaging during an interventional procedure.

[0008] Another advantage resides in providing more accurate and reliable interventional instrument tracking during an interventional procedure.

[0009] Another advantage resides in providing the foregoing advantages without the cost of providing ultrasound imaging and transrectal ultrasound (TRUS) probe hardware capable of performing live 3D ultrasound imaging.

[0010] A given embodiment may provide none, one, two, more, or all of the foregoing advantages, and/or may provide other advantages as will become apparent to one of ordinary skill in the art upon reading and understanding the present disclosure.

BRIEF DESCRIPTION OF THE DRAWINGS

[0011] The invention may take form in various components and arrangements of components, and in various steps and arrangements of steps. The drawings are only for purposes of illustrating the preferred embodiments and are not to be construed as limiting the invention.

FIGURE 1 diagrammatically shows a transrectal ultrasound (TRUS) probe, its two-dimensional (2D) image plane, an interventional instrument (illustrative biopsy needle) with ultrasound sensors disposed at pre-determined locations along the instrument, and a guidance grid for guiding the interventional instrument, with selected measured parameters including TRUS probe rotational angle indicated.

FIGURE 2 diagrammatically shows the TRUS probe of FIGURE 1 viewed along the axis designated in FIGURE 1, with the visualization plane with designated angle $\theta=0^\circ$ indicated along with two additional image planes accessed by rotating the TRUS probe over a positive or negative angle, respectively, indicated in grayed dashed lines.

FIGURE 3 diagrammatically shows an illustrative method for determination of the interventional instru-

ment tip and orientation using the device of FIGURE 1.

FIGURE 4 diagrammatically plots ultrasound sensor voltage as a function of angle (θ) of the TRUS probe for four sensors disposed at spaced-apart positions along a portion of the length of the interventional instrument.

FIGURE 5 illustrates a suitable approach for synchronizing data streams by interpolation.

FIGURE 6 illustrates a suitable approach for synchronizing data streams by data persistence.

FIGURE 7 diagrammatically illustrates determination of the interventional instrument tip and orientation based on determined 3D positions of the ultrasound sensors disposed at spaced-apart positions along a portion of the length of the interventional instrument, and optionally further based on the known entry point of the interventional instrument in the guidance grid.

DETAILED DESCRIPTION

[0012] As described above, while pre-procedural MR images and/or reconstructed 3D TRUS images provide 3D context for planning a transperineal intervention, 2D TRUS images are often used for live guidance during needle insertion. In a typical orientation, the sagittal ultrasound array of the probe is used in the live guidance. In view of this, the imaged plane is sometimes referred to as a "sagittal" plane. However, it is to be understood that this sagittal plane is with respect to the sagittal array of the TRUS probe, and is not necessarily aligned with the sagittal plane of the patient. For example, the TRUS probe may be rotated about its axis, and the procedure is still deemed to be under "sagittal image guidance", even though the imaged sagittal plane may be rotated or tilted respective to the sagittal plane of the patient. The terms "sagittal plane", "sagittal image guidance", and the like are to be understood as being used herein in this sense, i.e. the sagittal plane is the plane imaged using the sagittal array of the TRUS probe.

[0013] Use of 2D-TRUS imaging as the live guidance tool implicitly assumes that the needle lies in the sagittal plane imaged by the TRUS probe. However, due to anatomical constraints during needle insertion and needle-tissue interaction, it is generally not possible to ensure that the needle lies completely in the sagittal visualization plane during insertion, and in practice a given sagittal image usually contains only a portion of the needle. This leads to positional error and poor visibility of needles, and both degradation mechanisms increase with increasing deviation of the needle away from the ultrasound visualization plane. The needle is effectively "projected" onto the sagittal visualization plane, and the surgeon is not informed as to the 3D position and orientation of the needle in the body.

[0014] These problems could be overcome by performing 3D ultrasound imaging. However, this approach

has substantial disadvantages, including potentially increased ultrasound imaging equipment cost and more complex (and potentially confusing) live visualization in the 3D image space. Typically, the surgeon is most comfortable viewing the conventional two-dimensional sagittal plane, rather than attempting to visualize the needle position in a 3D perspective or otherwise-displayed three-dimensional space representation.

[0015] Interventional instrument tracking devices and methods disclosed herein advantageously retain the conventional approach of sagittal plane visualization via 2D ultrasound imaging, with the modification that the ability to rotate the TRUS probe about its axis is leveraged to extract additional three-dimensional information. While described with illustrative reference to transperineal prostate intervention using a TRUS probe, the disclosed approaches are readily employed in ultrasound-guided interventions directed to other anatomy such as the liver and/or for performing other procedures such as brachytherapy seed implantation, cryo-ablation, laser ablation, or so forth.

[0016] With reference to FIGURE 1, an ultrasound-guided intervention system includes an ultrasound imaging device **10** operatively connected with an ultrasound probe **12** (for example using a suitable connecting cable and mating connectors). In the illustrative example, the ultrasound probe is a trans-rectal ultrasound (TRUS) probe **12** sized and shaped for insertion into the rectum of a patient. Such a TRUS probe is commonly used for performing transperineal prostate intervention. The TRUS probe **12** is generally cylindrical and as such has a defined axis **14**. An ultrasound transducer array **16** is located on a sidewall of the cylindrical TRUS probe **12**, so as to perform sonication and imaging of a two-dimensional (2D) image plane **18**. A stepper device such as a cable, fitting or other mechanical component that can be moved manually or a stepper device such as a stepper motor **20** can be operated to automatically rotate the TRUS probe **12** about the axis **14**, for example under control of an electronic processor (e.g. microprocessor or microcontroller) of the ultrasound imaging device **10** (although a separate electronic processor performing this control is alternatively contemplated). In an alternative embodiment, the stepper motor **20** is omitted, the stepper device is not motorized, and instead the TRUS probe **12** is rotated manually by the surgeon or other surgical team member. Rotation of the TRUS probe **12** about the axis **14** revolves the ultrasound transducer array **16** about the axis **14**, and hence the image plane can be rotated to a chosen angle, which is designated herein without loss of generality as the (image) plane angle θ .

[0017] For the illustrative example of a transperineal prostate intervention procedure, live guidance during needle insertion usually employs ultrasound imaging of the sagittal plane. Accordingly, in the examples herein the visualization plane is designated as the sagittal plane and, for convenience, is designated as $\theta = 0^\circ$. It will be appreciated that other interventional procedures may

employ a different visualization plane appropriate for the position and orientation of the ultrasound probe used to guide the interventional procedure.

[0018] Transperineal prostate intervention also commonly utilizes a guidance grid **22** positioned abutting against the perineum of the prostate patient (not shown), and an interventional instrument **30** (e.g., a biopsy needle) is guided through an entry point of the guidance grid **22**. Use of the optional guidance grid **22** provides a convenient tool for systematically sampling a region of the prostate by successively inserting the biopsy needle **30** through designated entry points of the grid **22**. It will be appreciated that in other ultrasound-guided interventions, the grid **22** may not be used, or if used may be positioned against some other portion of the anatomy depending upon the target tissue or organ.

[0019] The interventional instrument **30** includes one or more ultrasound sensors disposed with the interventional instrument; without loss of generality, the illustrative example includes four such ultrasound sensors **S1**, **S2**, **S3**, **S4**; however, the number of sensors can be one, two, three, the illustrative four, five, or more. In this context, the term "disposed with" encompasses ultrasound sensors disposed on a surface of the instrument **30**, or disposed sensors disposed inside the instrument **30**, e.g. embedded within the instrument **30**. Each ultrasound sensor **S1**, **S2**, **S3**, **S4** emits a signal in response to sonication by an ultrasound beam from the ultrasound transducer array **16**. The illustrative ultrasound sensors **S1**, **S2**, **S3**, **S4** are piezoelectric sensors that generate an electrical signal (e.g. a voltage) in response to sonication. Such sensors suitably comprise a piezoelectric material such as a composite film of lead zirconate titanate (PZT) and polyvinylidene fluoride (PVDF) copolymers, although substantially any biocompatible material exhibiting sufficiently strong piezoelectric effect may be used, e.g. with electrodes for extracting the electric signal response. Each piezoelectric sensor **S1**, **S2**, **S3**, **S4** suitably includes electrical leads/traces (not shown), e.g. secured to or disposed with (i.e. on or in) the needle **30**, to carry the piezoelectric sensor voltage off the interventional instrument **30**. Alternatively, a micro-radio transmitter may be integrated with the piezoelectric sensor to wirelessly output the sensor voltage. In alternative embodiments (not illustrated), the ultrasound sensors may be ultrasound-reflective sensors that re-radiate received ultrasound pulses, in which case the sensor signal is the re-radiated ultrasound pulse which may be received by the same ultrasound transducer array **16** that sonicates the ultrasound-reflective sensors.

[0020] It is to be appreciated that the disclosed components, e.g. the ultrasound probe **12** with its stepper motor **20**, and the interventional instrument **30**, are merely illustrative examples, and other hardware configurations implementing desired functionality may be employed. For example, the stepper motor may be located elsewhere and operatively connected with the TRUS probe **12** via a driveshaft and optional gearing. In other

procedures, the ultrasound probe may be other than the illustrative TRUS probe **12**.

[0021] With continuing reference to FIGURE 1 and with brief reference to FIGURE 2, for 2D ultrasound imaging a linear array of ultrasound transducers **16**, or more generally an array of ultrasound transducers **16** with a generally linear form factor, are typically used. Such a transducer array with linear form factor is conveniently mounted on the side of a generally cylindrical probe body, so that the disclosed approach of rotating the ultrasound probe about an axis (e.g. the cylinder axis) is generally applicable to many interventional procedures employing 2D ultrasound guidance. FIGURE 2 shows an "end" view of the TRUS probe **12**, looking down the axis **14**, to illustrate how rotating the TRUS probe **12** away from the visualization plane (angle $\theta = 0^\circ$) **18** to a positive angle, or alternatively to a negative angle, results in probing 2D imaging planes that are tilted compared with the $\theta = 0^\circ$ visualization plane **18**. In general, the imaging planes probed by such rotation contain (or pass close to) the rotational axis **14** (although the illustrative axis **14** is outside of the visualized portion of the image plane since it is "behind" the transducer array **16**).

[0022] As seen in FIGURE 2, the biopsy needle **30** does not (in general) lie precisely in the visualization plane **18**. As a result, of the four ultrasound sensors **S1**, **S2**, **S3**, **S4**, only one sensor **S3** lies in the visualization plane **18**. Two sensors **S1**, **S2** lie at negative angles ($-\theta$) relative to the visualization plane **18**. One sensor **S4** lies at positive angle ($+\theta$) relative to the visualization plane **18**. In FIGURE 1, this is diagrammatically shown by having the portion of the needle **30** lying "behind" the visualization plane **18** as viewed from the perspective of FIGURE 1 shown in dashed lines. This includes the sensor **S4**.

[0023] The sensor **S3** lying in the visualization plane **18** can be localized as follows. The ultrasound probe **12** performs a 2D ultrasound sweep of the plane **18**. During this sweep, the ultrasound beam is swept across the 2D plane **18** and, at some point, this beam intersects and sonicates the sensor **S3**. In response, the piezoelectric sensor **S3** emits a sensor voltage that is detected. A voltmeter **32** detects this voltage output by the ultrasound sensor **S3**. (More generally, the piezoelectric sensor may output some other electric signal such as a change in capacitance or an electric current, and an electric signal detector detects the electric signal emitted by the piezoelectric sensor in response to the 2D ultrasound sweep). The detected sensor signal is time stamped. The location of the ultrasound sensor **S3** in the visualization plane **18** can be determined based on time-of-flight and ultrasound beam angle information derived from the ultrasound scanner **10**. In this case, the time of flight corresponds to the time interval between emission of the ultrasound beam pulse and detection of the sensor voltage. This time, multiplied by the speed of sound in the prostate tissue, provides the distance from the ultrasound transducer **16**. This distance along with the ultrasound beam

angle localizes the sensor **S3** in the plane **18**. (Note that if ultrasound-reflective sensors are used then the time-of-flight is the echo time interval between ultrasound pulse emission and detection of the re-emission - in this case, the time interval times the speed of sound is two times the distance from the ultrasound transducer to the reflective sensor, and so a factor of 0.5 is applied). The skilled artisan will recognize that this 2D localization approach is similar to that employed in 2D brightness mode (b-mode) imaging, except that the response signal is due to the sensor rather than ultrasound reflection from imaged tissue.

[0024] Such a 2D localization approach might also detect the out-of-plane sensors **S1**, **S2**, and **S4**, if the elevational ultrasound beam spread is such that it also partially sonicates these sensors. In this case, the sensor signal responsive to the ultrasound beam will be weaker due to the partial sonication; if the sensor is too far outside of the plane **18** then it may not be sonicated at all leading to sensor "invisibility". It will also be appreciated that the out-of-plane sensor, if sonicated, will be erroneously localized in the plane **18** (since it is assumed to lie in the plane) at the distance given by the time-of-flight. This positional error becomes larger with increasing distance of the sensor away from the visualization plane **18**.

[0025] With continuing reference to FIGURE 1, in embodiments disclosed herein, this error is corrected by the following approach implemented by a three-dimensional (3D) interventional instrument tracker **40** (e.g., in some implementations embodied by suitable programming of the microprocessor or microcontroller of the ultrasound imaging device **10** to control the transducer array **16** and stepper motor **20**, and reading the voltmeter **32**, to perform the disclosed approach). Instead of performing a single 2D ultrasound sweep of the single plane **18**, 2D ultrasound sweeps of a plurality of planes are performed. The various plane angles θ are reached via operation of the stepper motor **20**. The chosen plurality of planes encompasses (but does not necessarily include) the visualization plane **18**. For each 2D ultrasound sweep, a sensor signal emitted by each ultrasound sensor **S1**, **S2**, **S3**, **S4** in response to the 2D ultrasound sweep is detected. (In some cases the detected sensor signal may be a null signal, i.e. if the sensor is too far out of the plane of the 2D sweep then the detected sensor signal is zero). For each ultrasound sensor, an optimal plane is identified, from amongst the plurality of planes, for which the sensor signal emitted by the ultrasound sensor is highest. For this optimal plane, the ultrasound sensor is located using the time-of-flight and ultrasound beam angle information as already described for sensor **S3**. (In the case of sensor **S3**, the optimal plane is the visualization plane **18** since sensor **S3** lies in this plane **18**). Then, the location of each ultrasound sensor **S1**, **S2**, **S3**, **S4** is determined in a three dimensional (3D) reference space by transforming the location of each ultrasound sensor in its optimal plane to the 3D reference space. This is suitably done using a transform **42** parameterized by plane angle θ .

Spatial information for the interventional instrument **30** (e.g. tip position and orientation) are determined based on the locations of the one or more ultrasound sensors **S1, S2, S3, S4** in the 3D reference space. In performing this transformation, position of the ultrasound probe **12** and particularly the angle θ may be monitored by the TRUS probe tracker **34**; alternatively, the angle may be determined from rotational encoding of the stepper motor **20**. A visual indicator of the determined spatial information for the interventional instrument (e.g., its tip position and/or a line indicating its orientation) is displayed on a display **44** of the ultrasound device **10**, e.g. superimposed on or otherwise displayed with a displayed 2D ultrasound image of the visualization plane (e.g. b-mode ultrasound video). Alternatively, the 3D orientation of the needle **30** may be displayed in a pre-acquired and reconstructed 3D-TRUS image, or in a pre-acquired and reconstructed 3D MRI data set. It is also contemplated for the spatial information to include a prediction of the needle trajectory, e.g. by extending the current needle orientation.

[0026] The ultrasound probe tracker **34** tracks the position and orientation of the ultrasound probe **12** respective to the 3D reference space. The probe tracker **34** may employ any suitable probe tracking technology. For example, the probe tracker **34** may employ electromagnetic tracking and comprise an electromagnetic (EM) field generator and illustrative EM sensors **35** disposed with (e.g. on or in) the ultrasound probe **12**. Alternatively, the probe tracker may employ optical tracking technology that detects optical reflectors or LEDs disposed with (on or in) the ultrasound probe, or may employ a robotic encoder comprising a multi-jointed arm with spatial encoding joints, or so forth.

[0027] In summary, during needle insertion the TRUS probe **12** is rotated by a stepper device, e.g. by the stepper motor **20**, with the range of rotation of the image plane encompassing all the sensors **S1, S2, S3, S4** on the needle **30**. An optimal plane is identified for each sensor and its location in that optimal plane is determined. These locations are then transformed to a 3D reference space using a transform of the 2D location parameterized by the plane angle θ . The needle is preferably held stationary during probe rotation. In one approach, there can be 'start' and 'stop' buttons on the user interface, which the user can click to indicate the beginning and end of data acquisition during the probe rotation. The following quantities are acquired during the probe rotation: sensor voltages; 2D tracked sensor estimates in the plane of the 2D sweep based on time-of-flight and sonication beam angle in the 2D plane; and rotational positions (angles θ) of the TRUS probe. Each of these quantities (or each sample of these quantities) is time stamped. Interpolation may be employed to synchronize the data samples of the 2D positions and the angles θ .

[0028] Typically, it is not desired to have an ultrasound sensor positioned at the tip of the interventional instrument **30**, since this tip usually includes or embodies func-

tional apparatus for performing a biopsy, ablation procedure, or the like. Accordingly, in a suitable approach the sensors **S1, S2, S3, S4** have pre-determined (i.e. known) positions along the needle **30**, and the position of the tip relative to these known positions of the sensors is also pre-determined (known) and can therefore be obtained from the tracked 3D positions of the sensors **S1, S2, S3, S4** on the needle **30**. In general, at least two ultrasound sensors along the needle **30** are needed to determine its orientation; however, if the guidance grid **22** is used then the second position for determining orientation may be a pre-determined (known) entry point of the guidance grid **22** through which the interventional instrument **30** is guided.

[0029] With reference to FIGURE 3, an illustrative method for determination of the interventional instrument tip and orientation using the device of FIGURE 1 is described. In an operation **50**, the 2D ultrasound sweeps are performed over an angle range encompassing the visualization plane **18**, and the plane angle θ and sensor voltages are recorded as time stamped values. The angle range is also preferably selected to encompass the likely positions of most, or all, of the ultrasound sensors **S1, S2, S3, S4** on the needle **30**.

[0030] With continuing reference to FIGURE 3 and with further reference to FIGURE 4, in an operation **52** an optimal plane is identified for each sensor. This optimal plane is the plane for which the 2D ultrasound sweep yielded the largest sensor signal. FIGURE 4 illustrates this operation **52** by plotting sensor voltage as a function of plane angle θ (i.e. rotational position of the TRUS probe **12**). Note that FIGURE 4 plots the sensors with different arbitrary voltage offsets so that the four curves for the four sensors **S1, S2, S3, S4** are spaced apart. For each sensor, a peak is observed in its voltage-vs-angle plot, and the plane angle corresponding to this peak is the optimal plane angle (and hence indexes the optimal plane) for that sensor. Note that for the example of FIGURES 1 and 2 the sensor **S3** lies in the visualization plane **18**, so that the angle $\theta_3 = 0$ for this example. With continuing reference to FIGURE 3, in an operation **54** the 2D position of each sensor in its optimal plane is determined. This may be done using the time-of-flight and ultrasound beam angle information collected for the sensor in its optimal plane during the 2D ultrasound sweep of its optimal plane.

[0031] At this point, there are two pieces of information that have been collected for each sensor: its optimal plane (θ), and its 2D position in that optimal plane, denoted herein as $p(x,y)$. In the illustrative example, these two pieces of information come from different sources: the optimal plane is measured by the TRUS probe tracker **34**; whereas the position $p(x,y)$ in that plane is determined using the ultrasound device **10** and the voltmeter **32**. These values are synchronized in an operation **56**, for example by interpolation. In one suitable synchronization approach, data streams are acquired and stored in a common computer (e.g. the electronics of the ultrasound

imaging device **10**). Hence, the system clock can be used to regulate/interpret the data. Persistence or interpolation is used to "fill in" missing data from the data stream acquired at a lower acquisition rate (usually this is $p(x, y)$) and is then temporally matched to the data stream captured at a higher frame rate (usually the TRUS probe angle θ). The synchronized data streams can then be combined to estimate the 3D orientation of the needle.

[0032] With brief reference to FIGURE 5, an illustrative interpolation approach for performing the synchronization operation **56** is described. FIGURE 5 shows time stamps (column labeled "Time"), 2D sensor positions (column labeled "Needle tracking data"), and plane angle θ (column labeled "Probe tracking data"). To illustrate the interpolation consider that at time instant T_4 , there are missing entries in both the needle tracking and probe tracking data. The missing data may be interpolated using a weighted average of the data immediately preceding and succeeding the current time point T_4 . For the needle tracking data, this amounts to interpolating (X_1, Y_1) and (X_2, Y_2) , such as: $(a_4X_1 + b_4X_2, a_4Y_1 + b_4Y_2)$, where possible values for the weights a_4 and b_4 are: $a_4 = (T_6 - T_4)/(T_6 - T_3)$ and $b_4 = (T_4 - T_3)/(T_6 - T_3)$. Similarly, $c_4 = (T_5 - T_4)/(T_5 - T_3)$ and $d_4 = (T_4 - T_3)/(T_5 - T_3)$. Note that this method must be implemented with some time lag, since it utilizes data before and after the missing entry for the interpolation.

[0033] With brief reference to FIGURE 6, in an alternative embodiment for performing the synchronization operation **56**, the latest data can be persisted until the next data point for that stream arrives. This technique can be performed in real-time without any time lag, but may suffer from slightly reduced accuracy as compared with the interpolation approach of FIGURE 5.

[0034] With returning reference to FIGURE 3, in an operation **60** the 2D position of each sensor is transformed to the 3D reference space using the 2D-3D transformation(s) **42** which is parameterized by the plane angle θ . By "parameterized" it is meant that the transformation(s) **42** is dependent on the plane angle, or in other words the transform **42** operates to identify the location $P(x, y, z)$ of the ultrasound sensor in the 3D reference space according to $P(x, y, z) = T_{probe, \theta} \times p(x, y)$, where $T_{probe, \theta}$ is the transformation **42** and $p(x, y)$ is the location in the optimal plane. The precise formulation of the transformation **42** depends upon the selection, or definition, of the 3D reference space. In one embodiment, the transformation **42** is as follows:

$$P(x, y, z) = T_{EM, \theta}^{FG} \times T_{US}^{EM} \times p(x, y)$$

where T_{US}^{EM} is the transformation from the optimal 2D-US image plane to the EM sensors **35** attached to the ultrasound probe **12** (available from the US probe calibration of the EM tracking system). The US probe calibration is typically independent of the probe position and

is a pre-computed registration matrix. The other trans-

form $T_{EM, \theta}^{FG}$ is the transformation from the EM sensors **35** on the ultrasound probe **12** to the EM field generator (FG) of the TRUS probe tracker **34**, which establishes the 3D reference space coordinate system. This trans-

formation $T_{EM, \theta}^{FG}$ is a function of the optimal plane angle θ . More generally, if another probe tracking technology

is used, then the transformation $T_{EM, \theta}^{FG}$ is replaced by a suitable transformation into the 3D reference space coordinate system of that tracker.

[0035] With continuing reference to FIGURE 3 and with further reference to FIGURE 7, in an operation **62** spatial information for the interventional instrument **30** (e.g. its tip position and orientation) is determined based on the 3D sensor positions $P(x, y, z)$ and known inter-sensor and sensor-tip spacings. In one variant embodiment, this is also based on the pre-determined (known) entry point of the guidance grid **22** through which the interventional instrument **30** is guided. FIGURE 7 illustrates this approach by illustrating the 3D reference space with the locations $P(x, y, z)$ of each sensor **S1, S2, S3, S4** plotted. The entry point of the guidance grid **22** through which the interventional instrument **30** is guided is also plotted as a point **E**. The orientation of the needle **30** is then plotted as a line **L** passing through these points, suitably determined by linear regression. A tip position **T** of the tip of the interventional instrument **30** is suitably determined by the known tip-to-sensor spacings for the four sensors **S1, S2, S3, S4** measured along the best-fit line **L**. The tip position determined from the tip-to-sensor distance for each of the four sensors **S1, S2, S3, S4** may be averaged to provide greater accuracy.

[0036] In the illustrative embodiments, the stepper motor **20** is configured to rotate the ultrasound probe **12** about its axis **14**. In another contemplated embodiment, the stepper motor is configured to translate an ultrasound probe along a linear direction transverse to the 2D visualization plane (i.e. along a normal to the visualization plane), in which case the plurality of planes that encompasses the visualization plane is a set of parallel planes.

[0037] The invention has been described with reference to the preferred embodiments. Modifications and alterations may occur to others upon reading and understanding the preceding detailed description. It is intended that the invention be construed as including all such modifications and alterations insofar as they come within the scope of the appended claims.

Claims

1. A tracking device for tracking an interventional instrument (30) that has one or more ultrasound sensors (S1, S2, S3, S4) disposed with the interventional instrument, the tracking device comprising:

an ultrasound imaging device (10) including an ultrasound probe (12) configured to acquire a two-dimensional (2D) ultrasound image; and an electronic processor programmed to operate the ultrasound imaging device to perform an interventional instrument tracking method being characterized by:

operating the ultrasound imaging device to display a 2D ultrasound image of a visualization plane (18); performing 2D ultrasound sweeps of a plurality of planes that encompasses the visualization plane and, for each 2D ultrasound plane of the plurality of planes, detecting a signal emitted by each ultrasound sensor in response to the 2D ultrasound sweep of the plane; for each ultrasound sensor, identifying:

- an optimal plane of the plurality of planes for which the detected signal emitted by the ultrasound sensor is highest,
- the location of the ultrasound sensor in the optimal plane, and
- the location of the ultrasound sensor in a three-dimensional (3D) reference space based on the location of the ultrasound sensor in the optimal plane; and

determining spatial information for the interventional instrument, including at least one of tip location (T) and orientation (L) of the interventional instrument, based on the identified locations of the one or more ultrasound sensors in the 3D reference space.

2. The tracking device of claim 1 further comprising :

a stepper device connected to rotate the ultrasound probe (12) about an axis (14) to acquire the 2D ultrasound image at a plane having a plane angle (θ) controlled by the stepper device, wherein the plurality of planes span a range of plane angles that encompasses the plane angle of the visualization plane (18).

3. The tracking device of claim 2 wherein the ultrasound probe is a transrectal ultrasound (TRUS) probe (12).

4. The tracking device of claim 2 further comprising:

a guidance grid (22) configured to be positioned abutting against a perineum and to guide the interventional instrument (30) through an entry point of the guidance grid;

wherein the electronic processor determines the spatial information for the interventional instrument further based on a location (E) in the 3D reference space of the entry point of the guidance grid through which the interventional instrument is guided.

5. The tracking device of any one of claims 1-4 further comprising:

an ultrasound probe tracker (34) configured to track the location, in the 3D reference space, of the ultrasound probe (12); wherein the location $P(x,y,z)$ of the ultrasound sensor in the 3D reference space is identified as $P(x,y,z) = T_{probe,\theta} \times p(x,y)$ where $p(x,y)$ is the location of the ultrasound sensor in the optimal plane and $T_{probe,\theta}$ is a transformation (42) from the optimal plane to the 3D reference space which depends on the tracked location of the probe and a parameter θ of the optimal plane.

6. The tracking device of any one of claims 1-5 wherein the ultrasound sensors disposed with the interventional instrument (30) are piezoelectric sensors (S1, S2, S3, S4) and the tracking device further comprises:

an electric signal detector (32) configured to detect an electric signal emitted by each piezoelectric sensor in response to the 2D ultrasound sweep; wherein the electronic processor performs the detecting using the electric signal detector to detect the electric signal emitted by each piezoelectric sensor in response to the 2D ultrasound sweep.

7. The tracking device of any one of claims 1-5 wherein the ultrasound sensors (S1, S2, S3, S4) disposed with the interventional instrument (30) are ultrasound-reflective sensors that re-radiate received ultrasound pulses and the electronic processor performs the detecting using the ultrasound probe (12) to detect the re-radiated ultrasound pulse emitted by each piezoelectric sensor in response to the 2D ultrasound sweep.

8. The tracking device of any one of claims 1-7 wherein the electronic processor identifies the location of the ultrasound sensor in the optimal plane based on analyzing the sensor signal as a function of the timing of the beams fired by the ultrasound probe.

9. The tracking device of any one of claims 1-8 wherein the electronic processor identifies the location of the ultrasound sensor as time stamped samples, and identifies the parameter of the optimal plane as time

stamped samples, and the electronic processor further synchronizes the time stamped samples of the location of the ultrasound sensor and the time stamped samples of the parameter of the optimal plane by interpolation.

10. The tracking device of any one of claims 1-9 wherein the interventional instrument tracking method performed by the electronic processor further includes displaying a visual indicator of the determined spatial information for the interventional instrument (30) on the displayed 2D ultrasound image of the visualization plane (18).

Patentansprüche

1. Verfolgungsvorrichtung zum Verfolgen eines Eingriffsinstruments (30), das einen oder mehrere Ultraschallsensoren (S1, S2, S3, S4) aufweist, die an dem Interventionsinstrument angebracht sind, wobei die Verfolgungsvorrichtung Folgendes umfasst:

eine Ultraschall-Abbildungsvorrichtung (10) mit einer Ultraschallsonde (12), die so konfiguriert ist, dass sie ein zweidimensionales (2D) Ultraschallbild erfasst; und

einen elektronischen Prozessor, der so programmiert ist, dass er das Ultraschall-Bildgebungsgerät so steuert, dass es ein Verfolgungsverfahren des Eingriffsinstruments durchführt, das **gekennzeichnet ist durch**:

Betrieb des Ultraschall-Bildgebungsgerätes zur Darstellung eines 2D-Ultraschallbildes einer Visualisierungsebene (18);

Durchführung von 2D-Ultraschallabtastungen einer Vielzahl von Ebenen, die die Visualisierungsebene umfasst, und für jede 2D-Ultraschallebene der Vielzahl von Ebenen, Erfassen eines Signals, das von jedem Ultraschallsensor als Reaktion auf die 2D-Ultraschallabtastung der Ebene ausgesendet wird;

für jeden Ultraschallsensor, die Identifizierung von:

einer optimalen Ebene aus der Vielzahl der Ebenen, für die das vom Ultraschallsensor ausgesendete detektierte Signal am höchsten ist, der Position des Ultraschallsensors in der optimalen Ebene, und

der Position des Ultraschallsensors in einem dreidimensionalen (3D) Referenzraum auf Grundlage der Position des Ultraschallsensors in der optima-

len Ebene; und

Bestimmung der räumlichen Informationen für das Eingriffsinstrument, einschließlich mindestens einer von Spitzenposition (T) und Orientierung (L) des Eingriffsinstruments, basierend auf den identifizierten Positionen des einen oder der mehrerer Ultraschallsensoren im 3D-Referenzraum.

2. Verfolgungsvorrichtung von Anspruch 1, die ferner Folgendes umfasst:

eine Stufenvorrichtung, die so angeschlossen ist, dass sie den Ultraschallkopf (12) um eine Achse (14) dreht, um das 2D-Ultraschallbild in einer Ebene mit einem Ebenenwinkel (θ) zu erfassen, der von der Stufenvorrichtung gesteuert wird,

wobei die Mehrzahl von Ebenen einen Bereich von Ebenenwinkeln überspannt, der den Ebenenwinkel der Visualisierungsebene (18) umfasst.

3. Verfolgungsvorrichtung nach Anspruch 2, wobei die Ultraschallsonde eine transrektale Ultraschallsonde (TRUS) (12) ist.

4. Die Verfolgungsvorrichtung von Anspruch 2, die ferner Folgendes umfasst:

ein Führungsgitter (22), das so konfiguriert ist, dass es an einem Damm anliegt und das Eingriffsinstrument (30) durch einen Eintrittspunkt des Führungsgitters führt;

wobei der elektronische Prozessor die räumliche Information für das Eingriffsinstrument ferner auf Grundlage einer Position (E) im 3D-Referenzraum des Eintrittspunktes des Führungsgitters bestimmt, durch den das Eingriffsinstrument geführt wird.

5. Verfolgungsvorrichtung nach einem der Ansprüche 1 bis 4, die ferner Folgendes umfasst:

eine Ultraschallsonde (34), die so konfiguriert ist, dass sie die Position der Ultraschallsonde (12) im 3D-Referenzraum verfolgt;

wobei die Position $P(x,y,z)$ des Ultraschallsensors im 3D-Referenzraum identifiziert wird als $P(x,y,z) = T_{Sonde,\theta} \times p(x,y)$, wobei $p(x,y)$ die Position des Ultraschallsensors in der optimalen Ebene ist und $T_{Sonde,\theta}$ eine Transformation (42) von der optimalen Ebene in den 3D-Referenzraum ist, die von der verfolgten Position der Sonde und einem Parameter θ der optimalen Ebene abhängt.

6. Die Verfolgungsvorrichtung nach einem der Ansprüche 1 bis 5, wobei die an dem Eingriffsinstrument (30) angebrachten Ultraschallsensoren piezoelektrische Sensoren (S1, S2, S3, S4) sind und die Verfolgungsvorrichtung ferner Folgendes umfasst:
- einen Detektor (32) für elektrische Signale, der so konfiguriert ist, dass er ein elektrisches Signal erfasst, das von jedem piezoelektrischen Sensor als Reaktion auf die 2D-Ultraschallabtastung ausgesendet wird;
- wobei der elektronische Prozessor die Erfassung unter Verwendung des elektrischen Signaldetektors durchführt, um das von jedem piezoelektrischen Sensor als Reaktion auf die 2D-Ultraschallabtastung ausgesendete elektrische Signal zu erfassen.
7. Verfolgungsvorrichtung nach einem der Ansprüche 1 bis 5, wobei die Ultraschallsensoren (S1, S2, S3, S4), die an dem Eingriffsinstrument (30) angebracht sind, ultraschallreflektierende Sensoren sind, die empfangene Ultraschallimpulse zurückstrahlen, und der elektronische Prozessor die Erfassung unter Verwendung der Ultraschallsonde (12) durchführt, um den von jedem piezoelektrischen Sensor als Reaktion auf die 2D-Ultraschallabtastung ausgesendeten Ultraschallimpuls zu erfassen.
8. Verfolgungsvorrichtung nach einem der Ansprüche 1 bis 7, bei der der elektronische Prozessor die Position des Ultraschallsensors in der optimalen Ebene auf Grundlage der Analyse des Sensorsignals als Funktion des Zeitpunkts der von der Ultraschallsonde abgegebenen Strahlen identifiziert.
9. Verfolgungsvorrichtung nach einem der Ansprüche 1 bis 8, wobei der elektronische Prozessor den Ort des Ultraschallsensors als zeitgestempelte Samples erkennt und den Parameter der optimalen Ebene als zeitgestempelte Samples erkennt, und der elektronische Prozessor ferner die zeitgestempelten Samples des Ortes des Ultraschallsensors und die zeitgestempelten Samples des Parameters der optimalen Ebene durch Interpolation miteinander abgleicht.
10. Verfolgungsvorrichtung nach einem der Ansprüche 1 bis 9, wobei das durch den elektronischen Prozessor durchgeführte Verfahren zur Verfolgung eines Eingriffsinstruments ferner die Anzeige eines visuellen Indikators der ermittelten räumlichen Daten für das Eingriffsinstrument (30) auf dem angezeigten 2D-Ultraschallbild der Visualisierungsebene (18) umfasst.

Revendications

1. Dispositif de suivi permettant de suivre un instrument interventionnel (30), lequel comporte au moins un capteur à ultrasons (S1, S2, S3, S4) disposé dans l'instrument interventionnel, ledit dispositif de suivi comprenant:
- un dispositif d'imagerie par ultrasons (10) comprenant une sonde à ultrasons (12) conçue pour acquérir une image par ultrasons (2D) bidimensionnelle; et
- un processeur électronique programmé pour faire fonctionner le dispositif d'imagerie par ultrasons pour mettre en œuvre un procédé de suivi de l'instrument interventionnel **caractérisé par:**
- le fonctionnement du dispositif d'imagerie par ultrasons pour afficher une image par ultrasons 2D d'un plan de visualisation (18); la réalisation des balayages par ultrasons 2D d'une pluralité de plans, lesquels entourent le plan de visualisation et, pour chaque plan par ultrasons 2D de la pluralité de plans, par la détection d'un signal émis par chaque capteur à ultrasons en réponse au balayage par ultrasons 2D du plan; l'identification, pour chaque capteur à ultrasons, d'un plan optimal de la pluralité de plans pour lesquels le signal détecté émis par le capteur à ultrasons est le plus élevé, l'emplacement du capteur à ultrasons dans le plan optimal, et
- l'emplacement du capteur à ultrasons dans un espace de référence tridimensionnel (3D) en fonction de l'emplacement du capteur à ultrasons dans le plan optimal; et
- la détermination des informations spatiales pour l'instrument interventionnel, y compris au moins un emplacement de pointe (T) et une orientation (L) de l'instrument interventionnel, en fonction des emplacements identifiés de l'au moins un capteur à ultrasons dans l'espace de référence 3D.
2. Dispositif de suivi selon la revendication 1, comprenant en outre
- un dispositif étagé connecté pour faire tourner la sonde à ultrasons (12) autour d'un axe (14) pour acquérir l'image par ultrasons 2D dans un plan présentant un angle plan (θ) commandé par le dispositif étagé, dans lequel la pluralité de plans couvrent une plage d'angles plans, lesquels entourent l'angle plan du plan de visualisation (18).
3. Dispositif de suivi selon la revendication 2, dans le-

quel la sonde à ultrasons est une sonde à ultrasons transrectale (TRUS) (12).

4. Dispositif de suivi selon la revendication 2, comprenant en outre:

une grille de guidage (22) conçue pour être positionnée en butée contre un périnée et pour guider l'instrument interventionnel (30) à travers un point d'entrée de la grille de guidage; dans lequel le processeur électronique détermine les informations spatiales pour l'instrument interventionnel en fonction en outre d'un emplacement (E) dans l'espace de référence 3D du point d'entrée de la grille de guidage à travers lequel l'instrument interventionnel est guidé.

5. Dispositif de suivi selon l'une quelconque des revendications 1 à 4, comprenant en outre:

un dispositif de suivi de sonde à ultrasons (34) conçu pour suivre l'emplacement, dans l'espace de référence 3D, de la sonde à ultrasons (12); dans lequel l'emplacement $P(x,y,z)$ du capteur à ultrasons dans l'espace de référence 3D est identifié comme $P(x,y,z) = T_{sonde,\theta} \times p(x,y)$ où $p(x,y)$ est l'emplacement du capteur à ultrasons dans le plan optimal et $T_{sonde,\theta}$ est une transformation (42) du plan optimal vers l'espace de référence 3D, laquelle dépend de l'emplacement suivi de la sonde et d'un paramètre θ du plan optimal.

6. Dispositif de suivi selon l'une quelconque des revendications 1 à 5, dans lequel les capteurs à ultrasons disposés avec l'instrument interventionnel (30) sont des capteurs piézoélectriques (S1, S2, S3, S4) et le dispositif de suivi comprend en outre:

un détecteur de signal électrique (32) conçu pour détecter un signal électrique émis par chaque capteur piézoélectrique en réponse au balayage par ultrasons 2D; dans lequel le processeur électronique effectue la détection à l'aide du détecteur de signal électrique pour détecter le signal électrique émis par chaque capteur piézoélectrique en réponse au balayage par ultrasons 2D.

7. Dispositif de suivi selon l'une quelconque des revendications 1 à 5, dans lequel les capteurs à ultrasons (S1, S2, S3, S4) disposés avec l'instrument interventionnel (30) sont des capteurs réfléchissant les ultrasons, lesquels retransmettent les impulsions à ultrasons reçues et le processeur électronique effectue la détection à l'aide de la sonde à ultrasons (12) pour détecter l'impulsion à ultrasons rereçue émise par chaque capteur piézoélectrique en

réponse au balayage par ultrasons 2D.

8. Dispositif de suivi selon l'une quelconque des revendications 1 à 7, dans lequel le processeur électronique identifie l'emplacement du capteur à ultrasons dans le plan optimal en fonction de l'analyse du signal de capteur en fonction de la synchronisation des faisceaux envoyés par la sonde à ultrasons.

9. Dispositif de suivi selon l'une quelconque des revendications 1 à 8, dans lequel le processeur électronique identifie l'emplacement du capteur à ultrasons comme échantillons horodatés et identifie le paramètre du plan optimal comme échantillons horodatés, et le processeur électronique synchronise en outre les échantillons horodatés de l'emplacement du capteur à ultrasons et des échantillons horodatés du paramètre du plan optimal par interpolation.

10. Dispositif de suivi selon l'une quelconque des revendications 1 à 9, dans lequel le procédé de suivi de l'instrument interventionnel effectué par le processeur électronique comprend en outre l'affichage d'un indicateur visuel des informations spatiales déterminées pour l'instrument interventionnel (30) sur l'image par ultrasons 2D affichée du plan de visualisation (18).

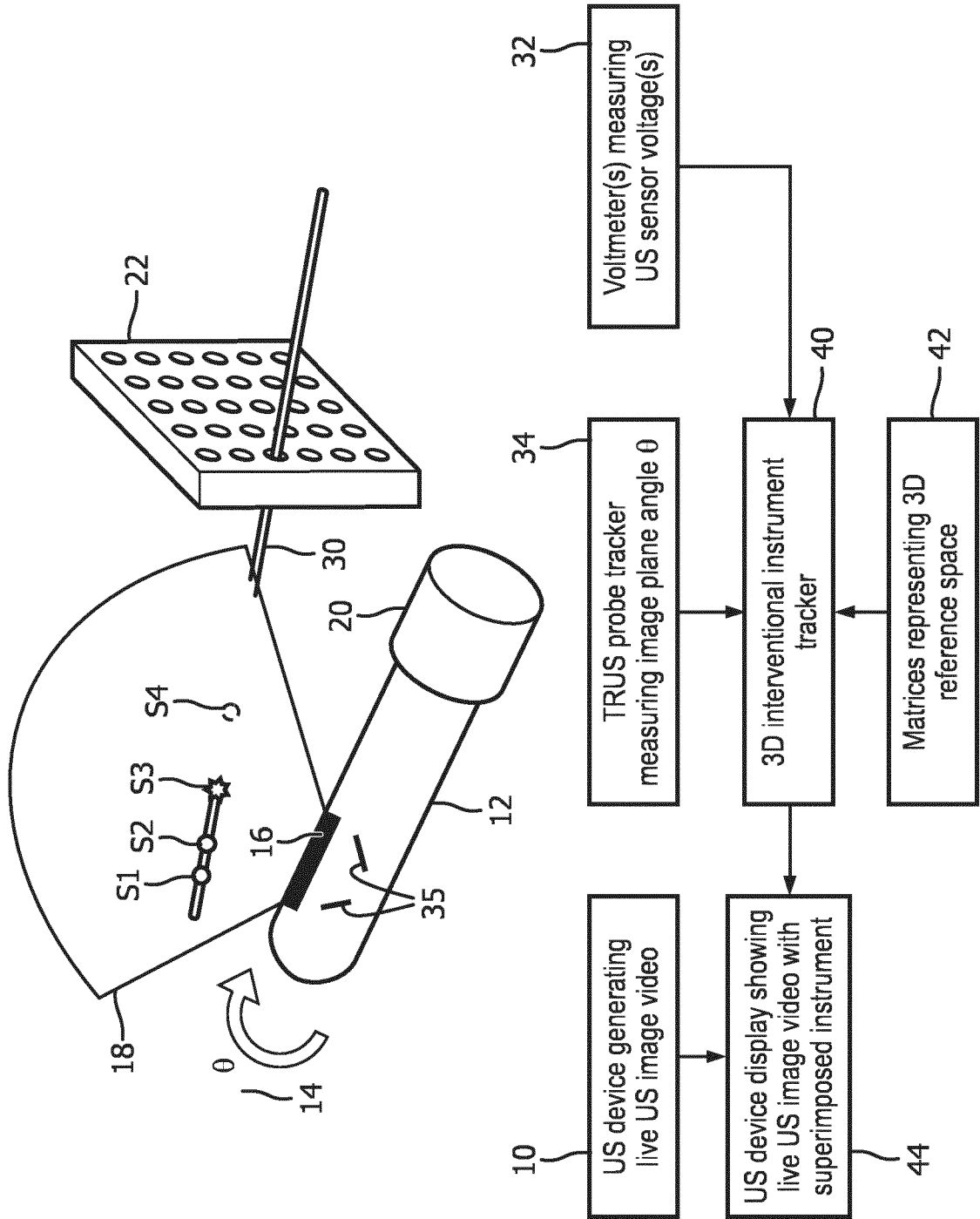


FIG. 1

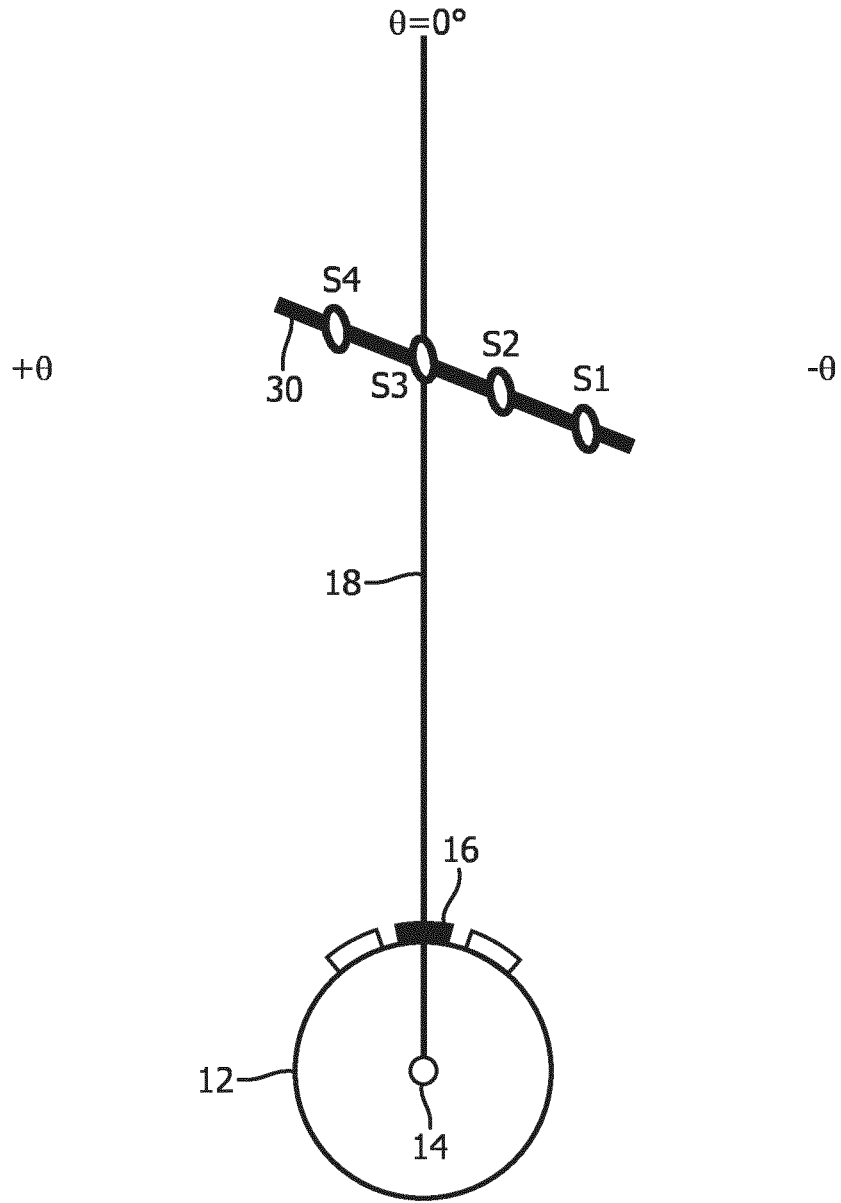


FIG. 2

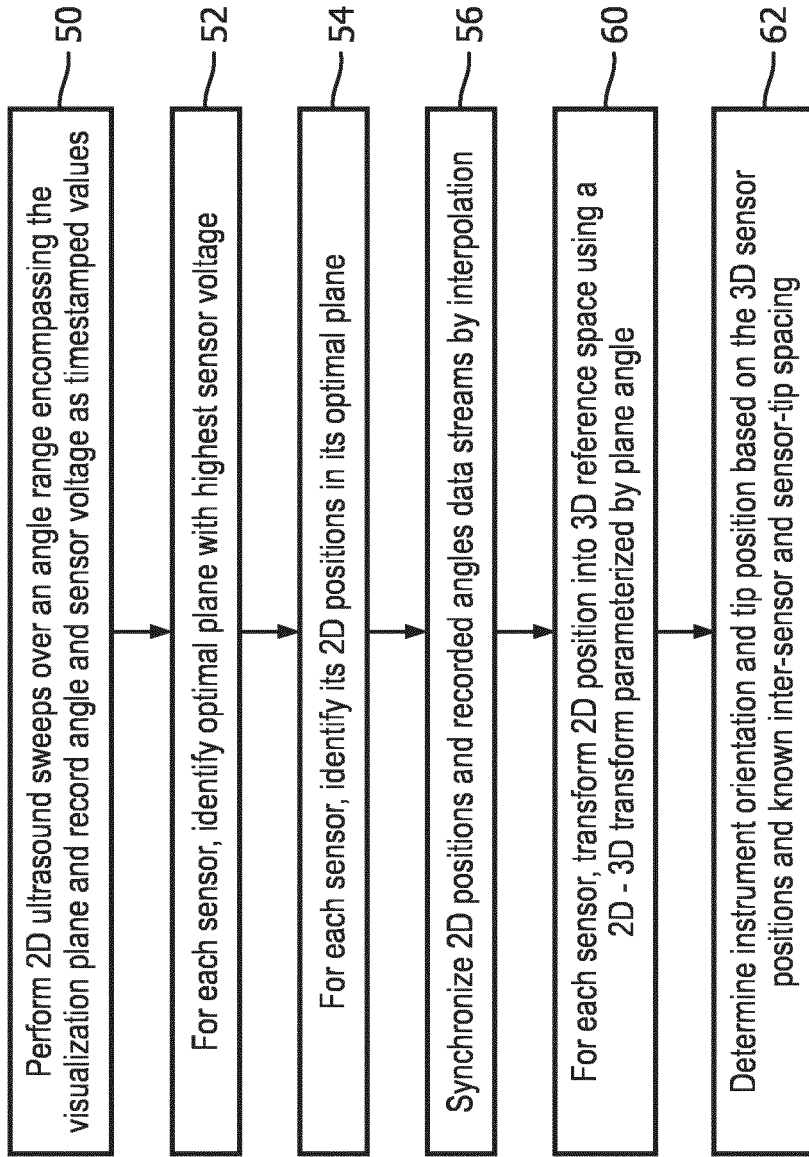


FIG. 3

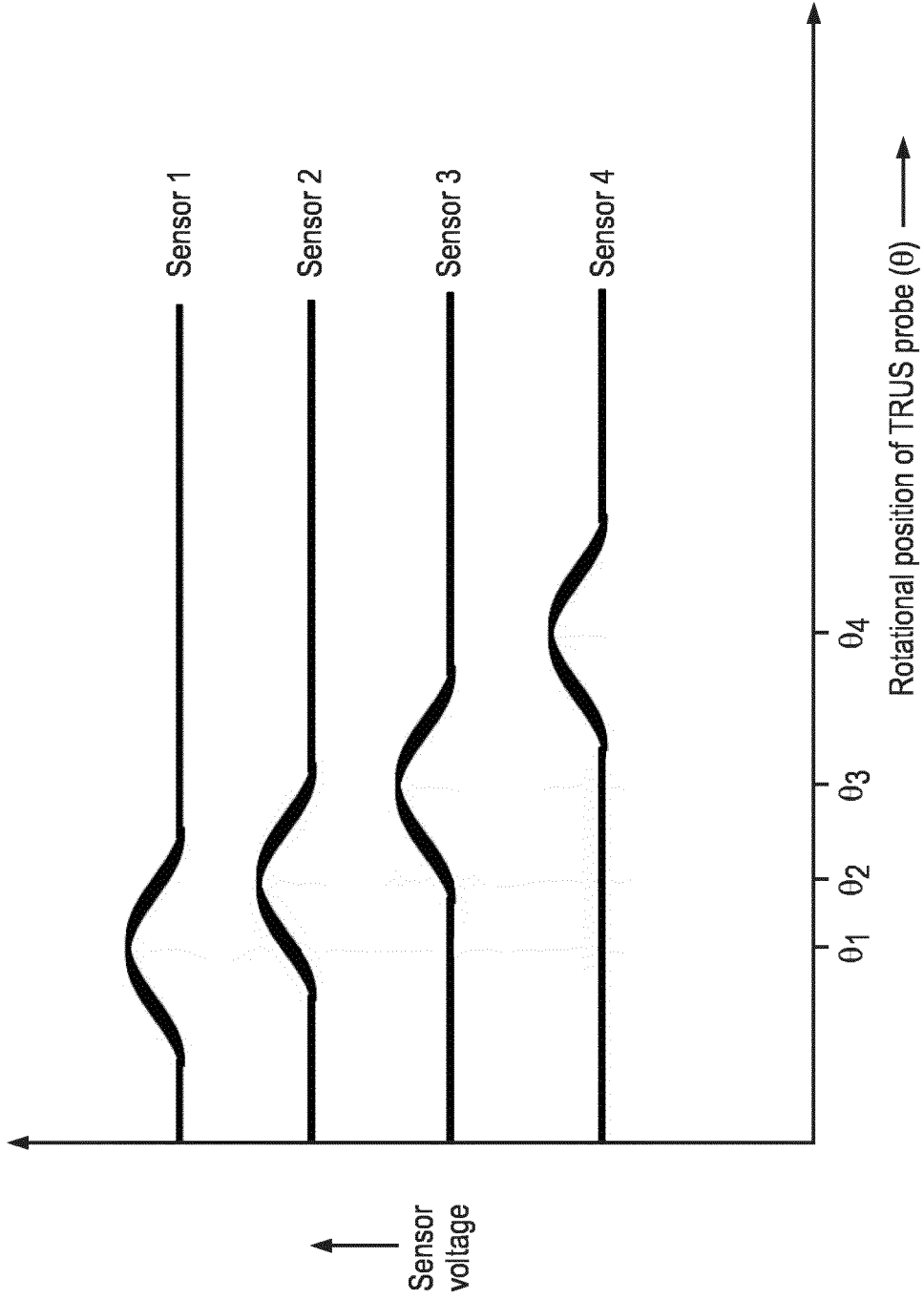


FIG. 4

T1			θ_1
T2			θ_2
T3		(X_1, Y_1)	θ_3
T4		$(a_4X_1+b_4X_2, a_4Y_1+b_4Y_2)$	$c_4\theta_3+d_4\theta_4$
T5		$(a_5X_1+b_5X_2, a_5Y_1+b_5Y_2)$	θ_4
T6		(X_2, Y_2)	θ_5
T7		$(a_7X_2+b_7X_3, a_7Y_2+b_7Y_3)$	θ_6
T8		(X_3, Y_3)	$c_8\theta_6+d_8\theta_7$
T9		$(a_9X_3+b_9X_4, a_9Y_3+b_9Y_4)$	θ_7
T10		$(a_{10}X_3+b_{10}X_4, a_{10}Y_3+b_{10}Y_4)$	θ_8
T11		(X_4, Y_4)	θ_9
T12		$(a_{12}X_4+b_{12}X_5, a_{12}Y_4+b_{12}Y_5)$	θ_{10}
T13		$(a_{13}X_4+b_{13}X_5, a_{13}Y_4+b_{13}Y_5)$	θ_{11}
T14		(X_5, Y_5)	θ_{12}

Probe tracking data

Needle tracking data

Time

FIG. 5

T ₁		θ ₁
T ₂		θ ₂
T ₃	(X ₁ , Y ₁)	θ ₃
T ₄	(X ₁ , Y ₁)	θ ₃
T ₅	(X ₁ , Y ₁)	θ ₄
T ₆	(X ₂ , Y ₂)	θ ₅
T ₇	(X ₂ , Y ₂)	θ ₆
T ₈	(X ₃ , Y ₃)	θ ₆
T ₉	(X ₃ , Y ₃)	θ ₇
T ₁₀	(X ₃ , Y ₃)	θ ₈
T ₁₁	(X ₄ , Y ₄)	θ ₉
T ₁₂	(X ₄ , Y ₄)	θ ₁₀
T ₁₃	(X ₄ , Y ₄)	θ ₁₁
T ₁₄	(X ₅ , Y ₅)	θ ₁₂
T ₁₅	(X ₅ , Y ₅)	θ ₁₃

Probe tracking data

Needle tracking data

Time

FIG. 6

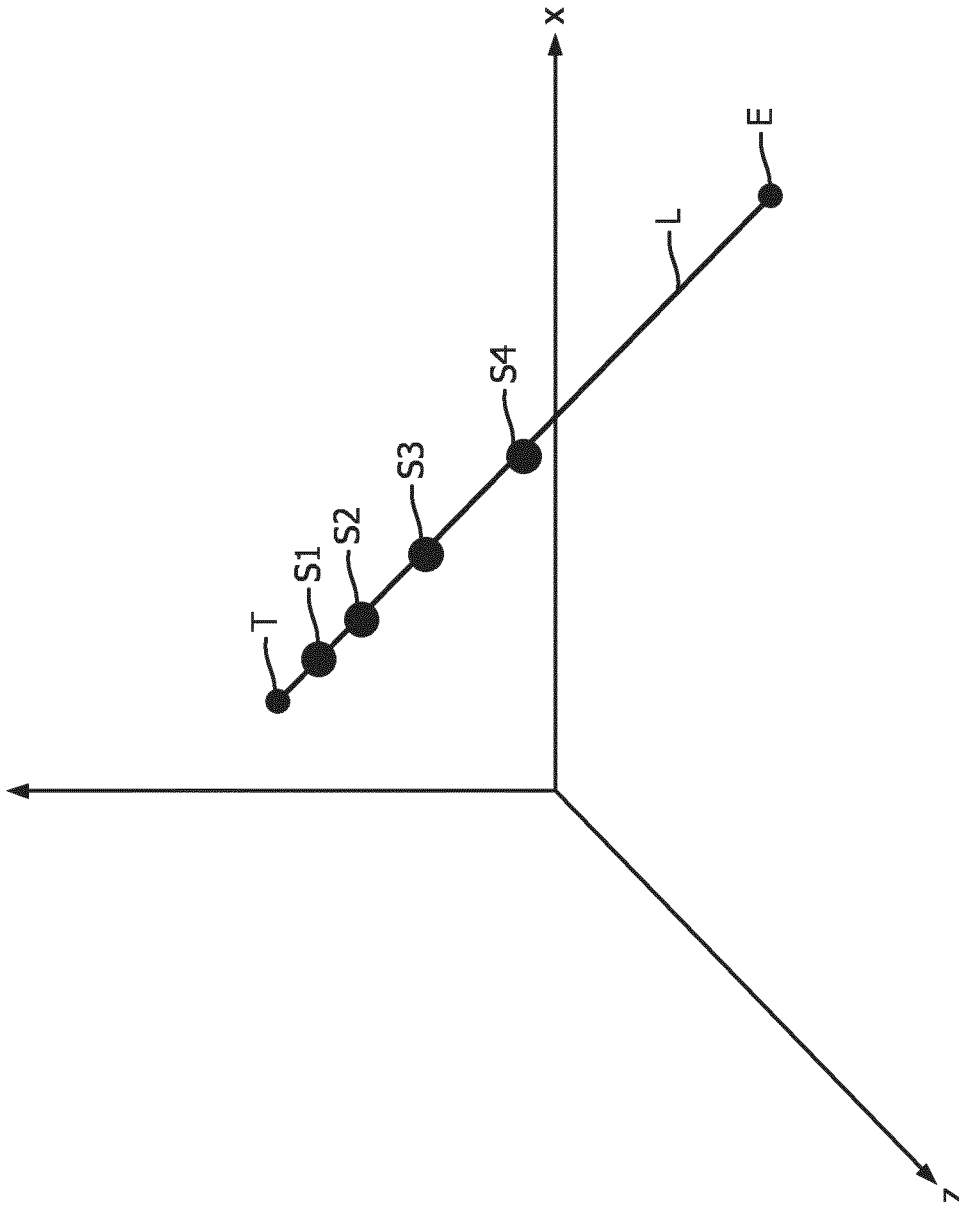


FIG. 7

REFERENCES CITED IN THE DESCRIPTION

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- **KRUECKER et al.** Fusion of transrectal ultrasound with pre-acquired MRI for prostate biopsy guidance. *MEDICAMUNDI*, 2008, 25-31 [0002]
- Tool Tracking for Ultrasound-Guided Interventions. **MUNG et al.** MICCAI. LNCS, 2011, vol. 6891, 153-60 [0003]

专利名称(译)	在2D超声引导下进行介入器械的3D监测		
公开(公告)号	EP3454757B1	公开(公告)日	2020-06-10
申请号	EP2017720108	申请日	2017-04-27
[标]申请(专利权)人(译)	皇家飞利浦电子股份有限公司		
申请(专利权)人(译)	皇家飞利浦N.V.		
当前申请(专利权)人(译)	皇家飞利浦N.V.		
[标]发明人	BHARAT SHYAM JAIN AMEET KUMAR BONILLAS VACA ANTONIO		
发明人	BHARAT, SHYAM JAIN, AMEET KUMAR BONILLAS VACA, ANTONIO		
IPC分类号	A61B8/08 A61B90/00		
CPC分类号	A61B8/0841 A61B34/20 A61B2017/00274 A61B2017/3413 A61B2034/2051 A61B2034/2055 A61B2034/2059 A61B2034/2063 A61B2090/367 A61B2090/3929 A61B2090/3983		
代理机构(译)	费尔利, PETER DOUGLAS		
优先权	62/334006 2016-05-10 US		
其他公开文献	EP3454757A1		
外部链接	Espacenet		

摘要(译)

使用超声成像设备 (10) 跟踪具有超声传感器 (S1 , S2 , S3 , S4 , ...) 的介入仪器 (30) , 该超声成像设备获取并显示可视化平面 (18) 的二维超声图像 , 并执行二维超声扫描通过旋转超声探头 (12) 获得的一定范围的平面角 (θ) , 并包含可视化的平面角。对于每个超声传感器 , 根据其在平面角度范围内的发射信号强度 , 找到一个最佳平面 , 然后通过分析传感器信号作为超声波发射光束定时的函数 , 将超声传感器放置在其最佳平面中。超声波探头。使用通过平面角度参数化的 transform (42) , 将它们各自最佳平面中的这些位置转换为3D参考空间 , 并显示从一个位置生成的介入器械的空间信息 (T , L) 的可视指示器 3D参考空间中的更多或更多超声传感器。

$$P(x, y, z) = T_{EMA} \times T_{US} \times p(x, y)$$