



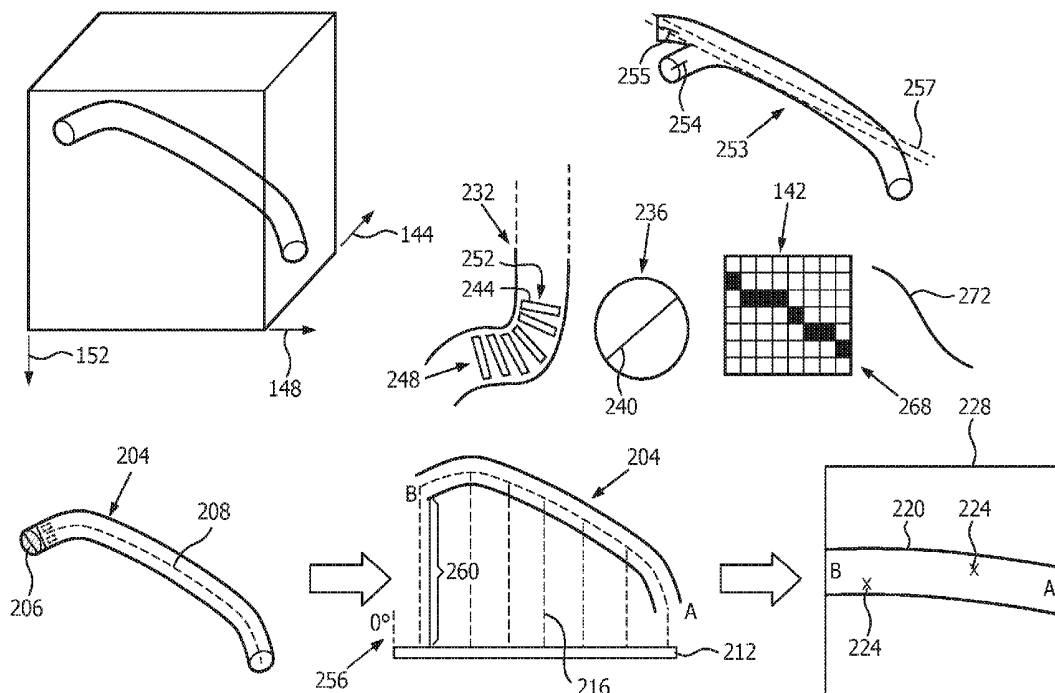
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(19) **United States**(12) **Patent Application Publication**
TAHMASEBI MARAGHOOSH(10) **Pub. No.: US 2017/0296141 A1**(43) **Pub. Date: Oct. 19, 2017**(54) **ULTRASOUND VISUALIZATION OF
CURVED STRUCTURES***A61B 8/00* (2006.01)*A61B 8/08* (2006.01)(71) Applicant: **KONINKLIJKE PHILIPS N.V.**,
EINDHOVEN (NL)(52) **U.S. Cl.**CPC *A61B 8/0891* (2013.01); *A61B 8/54*
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8/0841 (2013.01); *A61B 5/065* (2013.01);
A61B 8/481 (2013.01)(72) Inventor: **AMIR MOHAMMAD TAHMASEBI
MARAGHOOSH**, EINDHOVEN (NL)(21) Appl. No.: **15/517,218**(22) PCT Filed: **Oct. 30, 2015**(86) PCT No.: **PCT/IB2015/058395**

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30, 2014.**Publication Classification**(51) **Int. Cl.***A61B 8/08* (2006.01)*A61B 8/08* (2006.01)*A61B 8/08* (2006.01)*A61B 5/06* (2006.01)*A61B 8/08* (2006.01)*A61B 5/06* (2006.01)(57) **ABSTRACT**

An ultrasound imaging apparatus is configurable for acquiring a two-dimensional, flat image of a curved region (206) within a curved plane. The apparatus includes a transducer array for imaging the region; a processor for localizing the region with respect to the transducer array; and a processor for operating the transducer array for the imaging of the region and for projecting the region onto a two-dimensional (2D), flat image plane. Alternatively or in addition, an ultrasound imaging apparatus configurable for acquiring a 2D, flat image of a curved region within a curved plane includes a transducer array for imaging the region, the array having a face and transducer elements (142); a module for extracting a centerline of a curved object that contains the curved region; and a processor for: projecting the centerline (254) onto the face of the array; selecting, from among the elements, a set along the projection onto the face; receive beamforming, specifically using the set, to image the curved region and thereby acquire a curved image; and projecting the curved region onto a 2D, flat image plane.



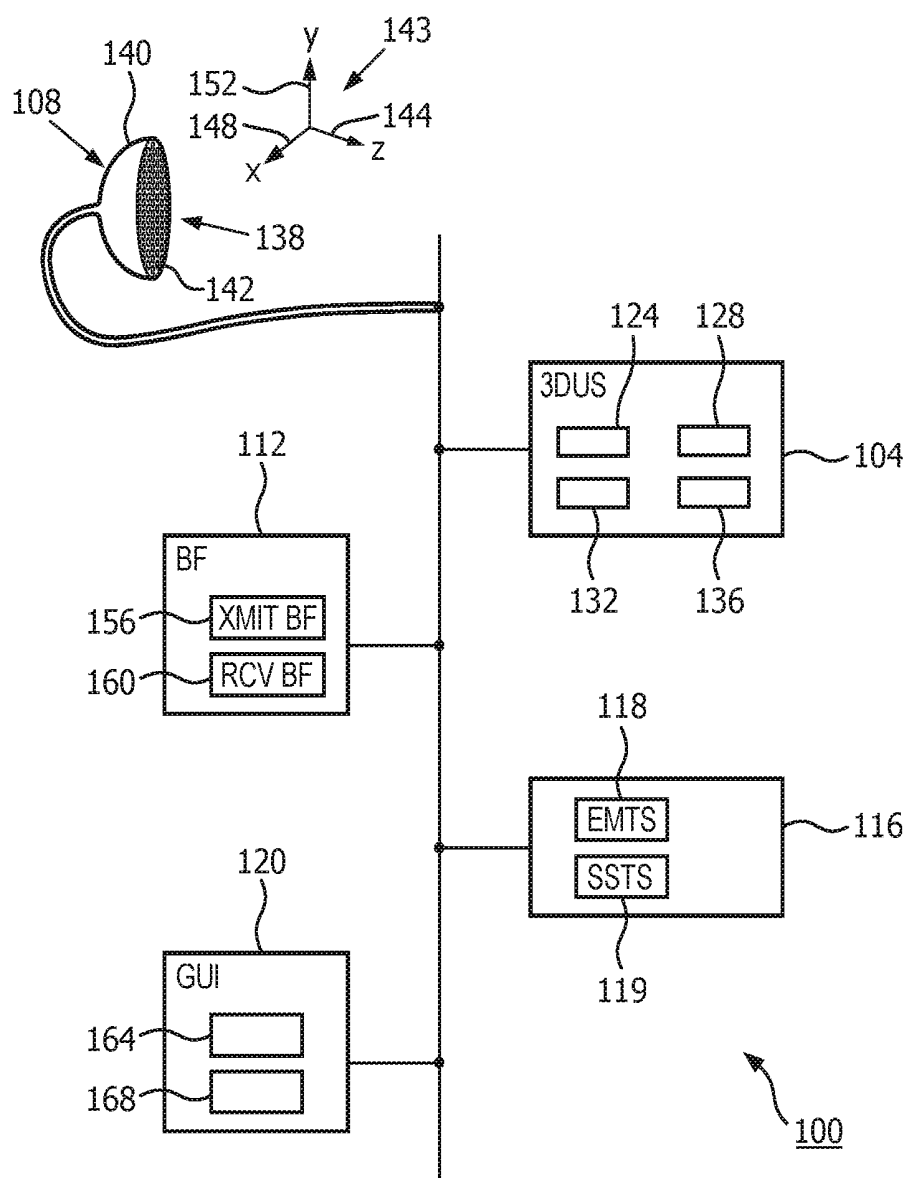


FIG. 1

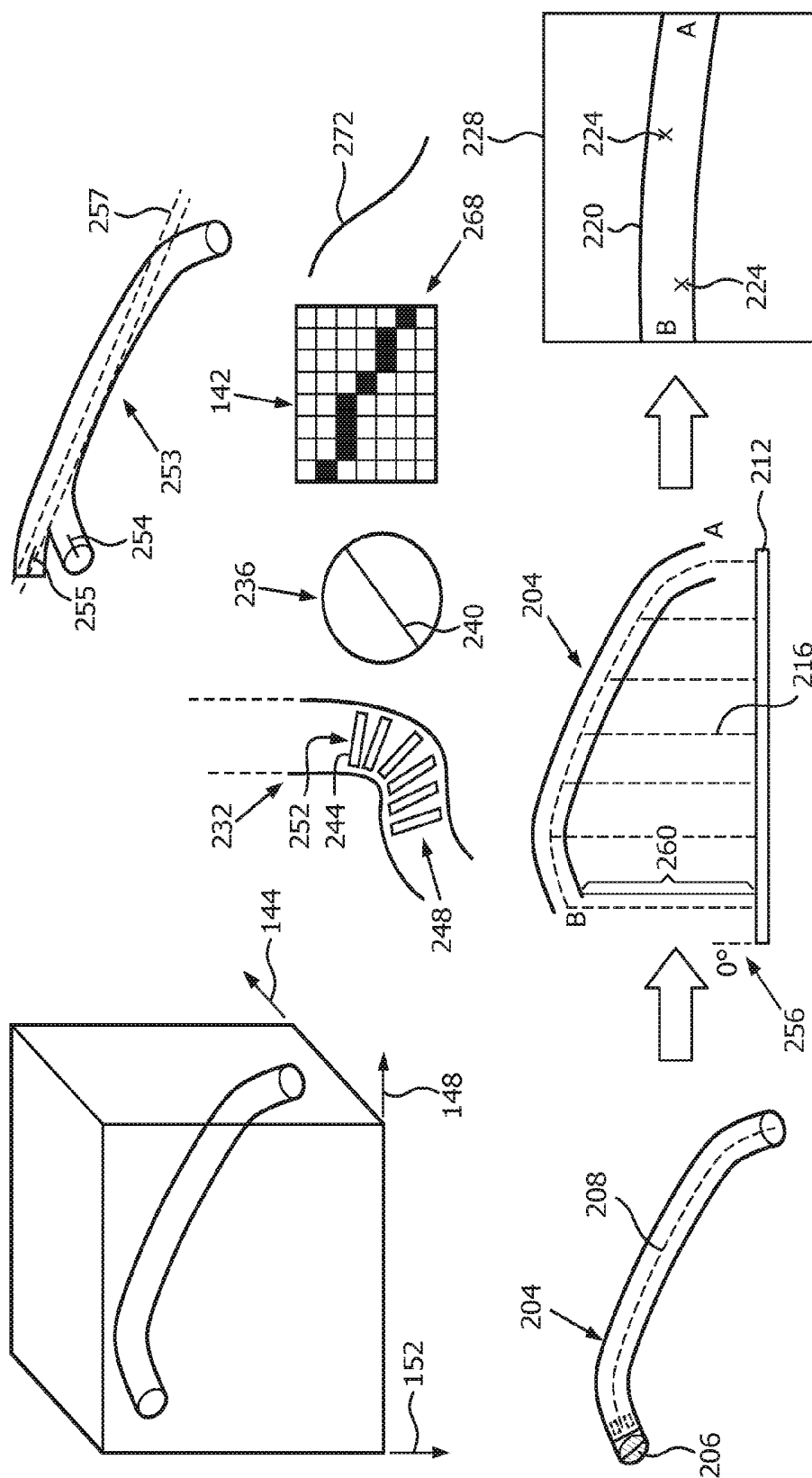
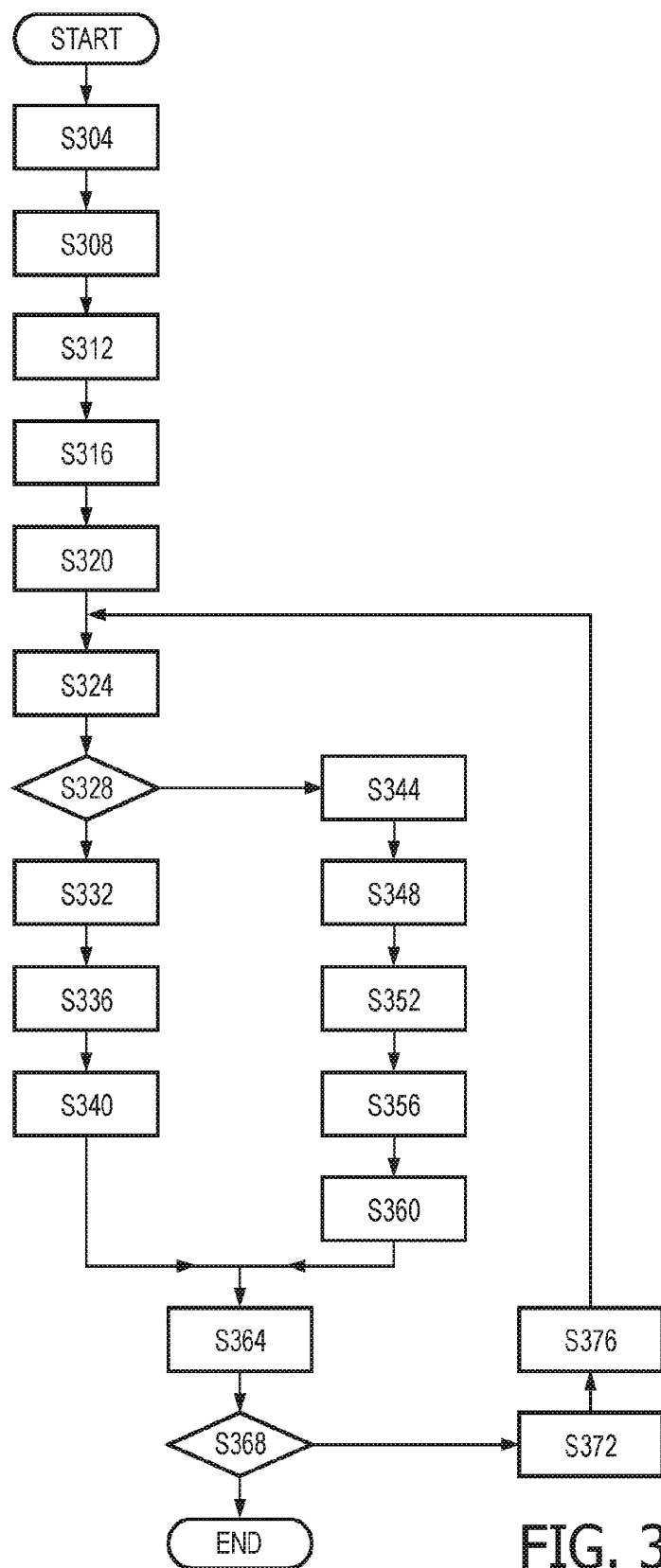


FIG. 2



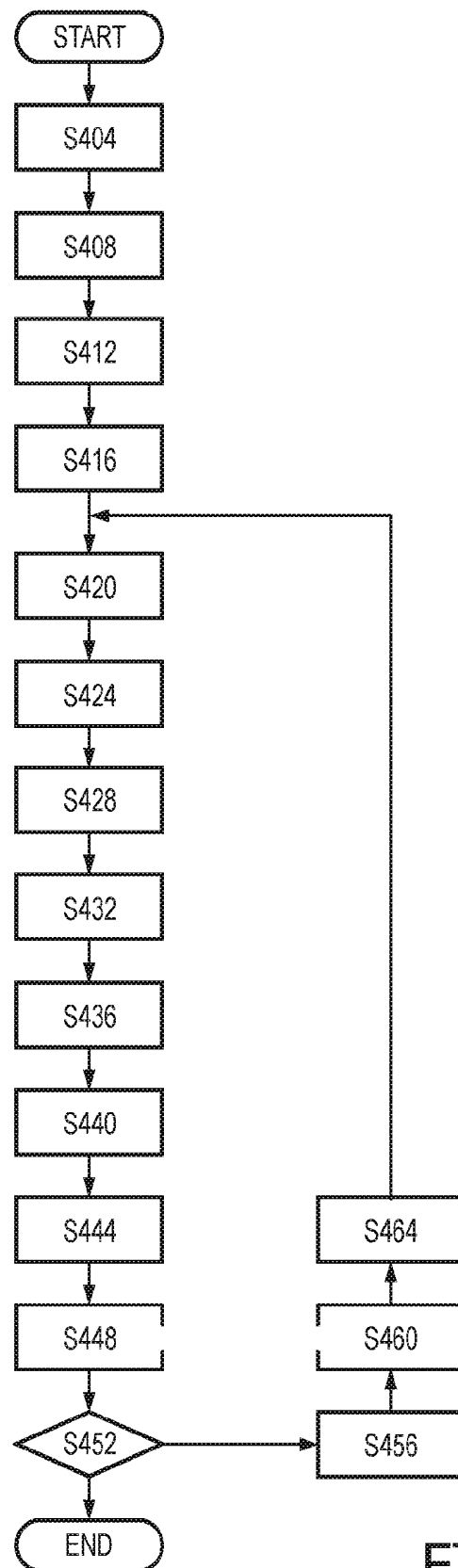


FIG. 4

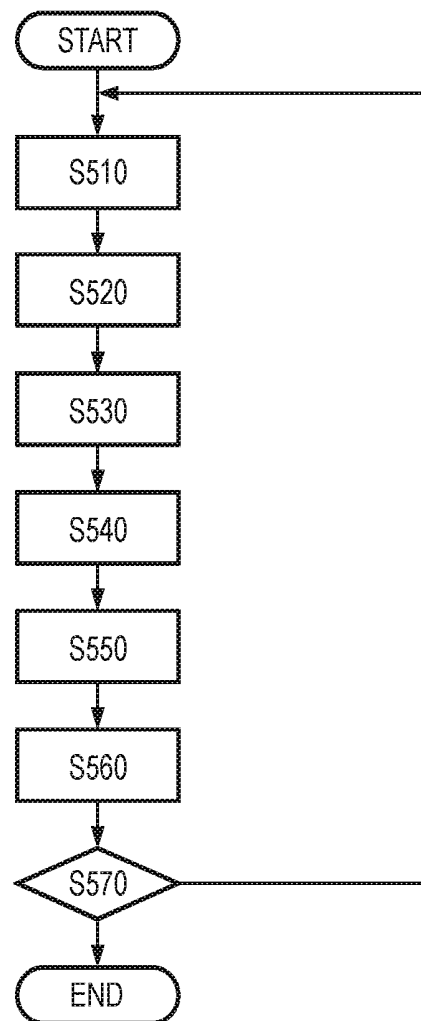


FIG. 5

ULTRASOUND VISUALIZATION OF CURVED STRUCTURES

FIELD OF THE INVENTION

[0001] The present invention relates to imaging a curved region within a curved plane and, more particularly, to imaging a two-dimensional, flat image of the region.

BACKGROUND OF THE INVENTION

[0002] U.S. Patent Publication No. 2013/0204124 to Duindam et al. (hereinafter “the ‘124 publication”), discloses a highly flexible, steerable surgical needle usable for biopsy or other procedures, the needle having a shape sensor. The entire disclosure regarding the shape sensor is incorporated herein by reference. In conjunction with pre-operative or intraoperative imaging, output of the sensor can be used in image coregistration. Deviation from a planned needle trajectory can, via the sensor, be detected, and corrected manually or automatically.

[0003] During insertion, the needle moves generally in a circular path governed by an asymmetric bevel in the needle tip. Rotating the needle shaft, as insertion proceeds, changes the direction of the bevel and thus the path. In addition, unintended deviations of the needle shaft due, for example, to buckling can be tracked.

[0004] While the ‘124 publication tracks sensory data in real time, it is unclear how images are displayed of the curved needle.

SUMMARY OF THE INVENTION

[0005] A curved structure, or object, such as a biopsy needle or a vascular structure cannot be visualized in an easy way using conventional display options available on an ultrasound machine. An image plane can be progressively shifted by a few increments in the normal direction to capture the entire structure piecemeal. However, this may distract the clinician or be difficult to perform, and does not include the whole span of the object in a single view of the structure. A three-dimensional rendering does not make clearly visible internally what is in the volume.

[0006] In an aspect of what is proposed herein, an ultrasound imaging apparatus is configured for acquiring a two-dimensional, flat image of a curved region within a curved plane. The apparatus includes an ultrasound transducer array for imaging the region. Also included is a localization processor configured for localizing the region with respect to the transducer array. Further included is an ultrasound imaging processor configured for operating the transducer array for the imaging of the region and for projecting the region onto a two-dimensional (2D), flat image plane.

[0007] In another aspect, an ultrasound imaging apparatus is configured for acquiring a 2D, flat image of a curved region within a curved plane. The apparatus includes an ultrasound transducer array for imaging the region. The array has a face and transducer elements. The apparatus also includes an image segmentation module configured for extracting a centerline of a curved object that contains the curved region. Further included is an ultrasound imaging processor configured for: projecting the centerline onto the face of the array; selecting, from among the elements, a set along the projection onto the face; receive beamforming, specifically using the set, to image the curved region and

thereby acquire a curved image; and projecting the curved region onto a 2D, flat image plane.

[0008] Details of the novel, technology for performing, onto a flat plane, a 2D projection of a curved region disposed within a curved plane are set forth further below, with the aid of the following drawings, which are not drawn to scale.

BRIEF DESCRIPTION OF THE DRAWINGS

[0009] FIG. 1 is a schematic diagram of one example of an apparatus for 2D displaying, onto a flat plane, of a curved region disposed within a curved plane, in accordance with the present invention;

[0010] FIG. 2 is a conceptual diagram exemplary of, and pertaining to, the apparatus of FIG. 1;

[0011] FIG. 3 is a flow chart illustrative and exemplary of 3D volumetric imaging operation according with the present invention;

[0012] FIG. 4 is a flow chart illustrative and exemplary of power Doppler imaging operation according with the present invention; and

[0013] FIG. 5 is a flow chart illustrative and exemplary of 3D sensor/transmitter-based imaging operation according with the present invention.

DETAILED DESCRIPTION OF EMBODIMENTS

[0014] FIG. 1 depicts, by way of illustrative and non-limitative example, an ultrasound apparatus **100** for performing a 2D projection of a curved region disposed within a curved plane. The apparatus **100** includes a 3D ultrasound (US) scanning processor **104**, an ultrasound imaging probe **108**, an ultrasound beamformer **112**, a sensor based localization processor **116**, and a graphical user interface (GUI) **120**.

[0015] The 3DUS scanning processor **104** includes an ultrasound imaging processor **124** and, for image processing based localization, a volumetric imaging localization processor **128**, optionally a power Doppler localization processor **132**, and an image segmentation module **136**.

[0016] The imaging probe **108** has an ultrasound transducer array **140** having elements **142**, and an acoustic image coordinate frame **143** defined by an axial direction **144**, an azimuthal or lateral direction **148**, and an elevational direction **152**. The array **140** has an ultrasound-communicative face **138** and is configured for acquiring a 3D image, either via a 2D matrix of the elements **142** or, for example, by motorized translation of a 1D array.

[0017] The beamformer **112** includes a transmit beamformer **156** and a receive beamformer **160**.

[0018] The sensor based localization processor **116** includes an electromagnetic tracking system **118** referred to hereinafter as an EMTS, and/or a shape sensor tracking system **119** referred to hereinafter as an SSTS. The EMTS may include in-situ position sensors onboard a curved object, such as a surgical needle or other medical intervention tool, being tracked.

[0019] The GUI **120** has 2D display **164**, with a 2D display screen, and a user control **168** configured in any known and suitable manner with any one or combination of keyboard, touchscreen, slider, joystick, trackball, etc.

[0020] FIG. 2 portrays acquisition of an image of a curved region and projection onto a flat plane. A curved plane is spatially continuous in two orthogonal directions but deviates from being flat. For example, a tubular object **204**

contains a curved region **206**, part of which is shown in FIG. 2 with dots to indicate the region continues longitudinally through the object. The tubular object **204** has a centerline, or midline, **208**. The curved region **206** contains the centerline **208**. A curved plane can be constructed which fully contains the curved region **206** and thus the centerline **208**. The tubular object may be elongated, such as in the case of an elongated segment of a blood vessel or curved surgical needle. The centerline **208** may be projected onto an image plane **212** as indicated in

[0021] FIG. 2 by lines **216** of projection. An outline **220** of the vessel segment **204** is projected, as are field points **224** aligned with the centerline **208**. The field points aligned can make up a generally planar surface which curves with the tubular object **204**, and which constitutes the curved region **206**. Surrounding anatomy **228** may likewise be projected in alignment with the centerline **208**. Here too, the surrounding anatomy field points that are projected may extend the generally planar surface. The centerline **208** and other aligned area of the image, i.e., the extended generally planar surface, make up a two-dimensionally continuous, yet curved, sub-plane within the curved plane. The curved sub-plane, which contains the curved region **206**, is projected onto a flat, 2D plane such as the image plane **212** shown in FIG. 2.

[0022] The aligned area for a tubular object **232** is formable by taking thin strips that bisect a cross-section **236** of the tubular object. A side view **240** of a thin strip is shown in FIG. 2. The thin strip traverses the interior of the tubular object **232** but, for simplicity of illustration in FIG. 2, its depiction does not extend into walls of the tubular object. The thin strip **244** itself is shown in the alongside perspective view of the tubular object **232**. Although there are 360° worth of options on how the thin strip might bisect the cross-section **236**, a thin-strip-specific orientation in which the maximum area is projected onto the image plane **212** can be selected. Other strips **248** are constructed for the somewhat twisting tubular object **232**. The strips **244**, **248** can be made very thin, so as to each correspond to, as well as go through, a respective field point on the centerline **208**. Adjacent pairs of the strips **244**, **248** may have intervening gaps, due to vessel twisting and directionality changes and due to the angle of view. Optionally, the gaps can be filled by 3D interpolation. In either case, a generally planar surface **252** is available for subsequent projection onto the image plane **212**. The generally planar surface **252** can be extended for surrounding anatomy **228**. The extended surface is projectable onto the image plane **212** which can then be displayed on the 2D display **164**.

[0023] For more complex tubular objects, such as a bifurcated vessel segment **253**, the bisecting, thin strips may, at a bifurcated portion, extend through respective centerlines **254**, **255** of both bifurcated branch portions. The main branch is an elongated curved object containing an elongated curved region **206**, and the bifurcating branch is, analogously, a second elongated curved object containing a second elongated curved region.

[0024] Although the image plane **212** is shown in FIG. 2 at a particular orientation **256** (i.e., of zero degrees) with respect to the tubular object **204**, another orientation may be selected.

[0025] An image plane **257** is depicted which, in terms of deviations **260** from the first and second centerlines **254**, **255** of the tubular object **264**, has an optimal least squares fit to

the two centerlines. In the case of a simple vessel segment being examined, an optimal least squares fit can be found to the single centerline **208**.

[0026] By comparison and by way of example, if the first-mentioned image plane **212** is prepared for the projection by translating the image plane in a normal direction up toward the centerline **204** to minimize the sum of squares of the deviations **260**, the orientation **256** of the image plane results in a least squares result that is sub-optimal. Accordingly, the projection may optionally be done, instead, onto the image plane **257** that has been optimally oriented, by a rotation of for example 30 or 36 degrees, so as to achieve an optimal least squares fit.

[0027] If, the optimally fitted plane is utilized, the orientation **256** that defines this plane of projection is determined prior to generation of the thin strips **244**, **248**. Based on a view normal from the optimally fitted plane, the strips can be rotationally oriented about the centerline **208** for maximum projection area onto the plane.

[0028] It is noted that that the curved region **206** need not be elongated. A patch of surface coronary tissue, for example, can be volumetrically imaged, localizing the patch to the transducer array **140**, and projected onto a pre-designated or optimally fitted imaging plane for display as a B-mode image.

[0029] FIG. 3 is one example of a procedure for imaging a curved region **206**, such as in vasculature, that is disposed within a curved plane. A 3D image is acquired (step S304). Ultrasound contrast agent, such as microbubbles, may be administered (step S308). The user, on the GUI **120**, scans through B-mode images to find, and interactively indicate, a vessel starting point and a vessel ending point (step S312). The two points might be indicated from different B-mode images. The two points, and an ultrasound image of the delimited vessel segment **204**, are stored. Additional points are user-selectable for bifurcated vessel segments **253** (step S316). The vessel segment **204** is segmented, in the imaging sense, by virtue of the delimitation and the contrast agent (step S320). The centerline **208** of the vessel segment **204** and the vessel's cross-sectional contours are identified. The same is performable for the bifurcated vessel segment **253** (step S324). A method for achieving step S324 is disclosed in U.S. Patent Publication No. 2013/0064435 to Taerum (hereinafter "the '435 publication"), from paragraphs [0027]-[0065] the disclosure of which is incorporated herein by reference. A snake, or "active contour", may be used, as in the '435 publication, to determine vessel contours. Two alternative projection modes are available at this point. In a first mode (step S328), a least squares analysis is done to find the optimal orientation **256** of the image plane **257** in fitting it to the centerline(s) **254**, **255** (step S332). Alternatively, a specific, predetermined orientation can be designated. The curved region **206** is then determined by the steps discussed herein above and thereby localized with respect to the transducer array **140** or, more specifically, to the acoustic image coordinate frame **143** of the array (step S336). The curved region **206** and optionally its surroundings are then projected onto the designated or optimally fitted image plane **257** (step S340). The surrounding anatomy might not be appended to the curved region **206**. For example, the vessel might be imaged in isolation for analysis such as in the '435 publication. Or, for instance, imaging on the optimally oriented image plane **257** might occur interleavably with the extracted image of merely the curved region **206**. If,

instead, the other projection mode is chosen (step S328), the centerline 208 is projected onto the ultrasound transducer face 138 (step S344). From among the transducer elements 142, a set 268 is selected along the projection (step S348). The set 268 is elongated, as seen in FIG. 2. It may be given greater width to make the receive beamforming more robust. Transmission, which is not restricted transducer-element-wise, is performed (step S352). The echo is beamformed on receive using the set 268 of transducer elements 142 (step S356). The receive beamforming is performable according to the well-known delay-and-sum technique, the active elements on receive being limited to the set 268. To the extent the centerline 208 is curved in the projection, the image acquired by the receive beamforming will be a “curved” B-mode image plane 272. This curved region, or curved image, is projected onto a 2D flat image plane, as in the other projection mode selectable at step S328 (step S360). For either projection mode, the 2D flat image plane is displayed (step S364). If the displaying is to continue (step S368), a 3D image is acquired (step S372). The object being imaged is identified again in the current 3D acquisition (step S376). This is accomplished by pattern matching, e.g., speckle matching, to the image information stored in step S316. Return is made to the centerline extracting step S324, thereby affording dynamic tracking via live imaging.

[0030] An alternative routine for imaging vasculature is presented in FIG. 4. A 3D power Doppler image of the vasculature is acquired (step S404). The user scans through image planes to find two, or more, vessel points that delimit the vasculature to be imaged (step S408). The two, or more, points and an image near the points are saved (step S412). The power Doppler imaging is used to segment the curved blood vessel (step S416). A method as in the ‘435 publication is utilized to identify the centerline 208 of the vessel segment 204 and the vessel’s cross-sectional contours (step S420). The ‘435 publication mentions use of volumetric pixel intensity values in segmenting a vessel. Power Doppler intensities can serve this purpose. A least squares analysis is done to find the optimal orientation 256 of an image plane 257 in fitting it to the centerline(s) 254, 255 (step S424). Alternatively, a specific, predetermined orientation 256 can be designated. The curved region 206 is then determined by the steps discussed herein above and thereby localized with respect to the transducer array 140, i.e., the acoustic image coordinate frame 143 (step S428). The curved region 206 is then projected onto the designated or optimally fitted, flat image plane (step S432). The transducer elements 142 are switched to B-mode (step S436). A B-mode image is acquired (step S440). The image plane of the B-mode image can be the optimally fitted image plane derived in step S424. The acquired B-mode image is displayed (step S444). The projected curved region 206 is superimposed on the displayed B-mode image (step S448). If processing is to continue (step S452), the transducer elements 142 are switched back to power Doppler mode (step S456). A 3D power Doppler image is acquired (step S460). The vessel being imaged is identified again in the 3D acquisition (step S464). This is accomplished by pattern matching to the image information stored in step S412. Return is made to the centerline extracting step S420.

[0031] A straight medical needle is a specular object, and will not reflect ultrasound in a way conducive to good imaging unless the ultrasound beam is approximately nor-

mal to the needle. After an initial image, the beam can be steered into a normal direction.

[0032] Such a technique is less effective for curved needles.

[0033] Referring to FIG. 5, in an exemplary technique for curved objects other than vasculature, such as medical interventional instruments, one or more structures are fixed to the object (step S504). The structures constitute at least one sensor, at least one ultrasound transmitter, or a combination of at least one sensor and at least one ultrasound transmitter. The sensor may be, for example, an EM sensor, a shape sensor, optical sensor, or an ultrasound receiver. Equipping an interventional tool in this manner is described in commonly-assigned U.S. Patent Publication No. 2013/0041252 to Vignon et al., in paragraphs [0003], [0005], and [0075]-[0083] among others. Disclosure on the same topic is found also in commonly assigned U.S. Patent Publication No. 2014/0121502 to Vignon et al., in paragraphs [0075], [0080], [0081], and [0089]. The disclosure in both publications relating to equipping an interventional tool in this manner is incorporated herein by reference. In the case of a single EM sensor onboard the tool, for example, an EM tracking system can be implemented in which both location and orientation information are derived from communication with the onboard sensor. Given a stiff tool, its position and location is then localized. For structures such as ultrasound receivers and ultrasound transmitters whose individual communication, from onboard the object, provides location but not useful orientation information, a plurality of such structures can determine orientation. In the case of a flexible tool, shape sensors are commonly used. An example is the ‘124 publication mentioned herein above. The entire disclosure including paragraphs [0007]-[0022] and [0045]-[0052], relating to the description herein above, of this publication is incorporated herein by reference. Position and/or shape sensing is also discussed in U.S. Pat. No. 7,772,541 to Froggatt et al. Column 6, line 65 to column 12, line 41 is incorporated herein by reference.

[0034] As provided in FIG. 5, the sensor-based localization processor 116 communicates, via the EMTS 118 or SSTs 119, with the one or more sensors or transmitters fixed to the curved object (step S510). The object is registered to the acoustic image coordinate frame 143, and thereby localized (step S520). The registration can occur via a transformation from tracking space to a reference space, and then from the reference space to the acoustic image coordinate frame 143. Or the transformation can be performed directly from the tracking space to the acoustic image coordinate frame 143. The object or its outline is projected onto a flat 2D image plane (step S530). The flat 2D image plane can be pre-designated or optimized in its orientation 256 via a least squares analysis. A B-mode image is acquired of the same image plane (step S540). The B-mode image is displayed (step S550). A graphic symbol depiction of the object, such as spatially its outline, is superimposed for display on the B-mode image (step S560). If displaying is to continue (step S570), return is made to the start of the routine at step S510, thereby providing live imaging for tracking the object.

[0035] An ultrasound imaging apparatus is configurable for acquiring a two-dimensional, flat image of a curved region within a curved plane. The apparatus includes a transducer array for imaging the region; a processor for localizing the region with respect to the transducer array; and a processor for operating the transducer array for the

imaging of the region and for projecting the region onto a two-dimensional (2D), flat image plane. Alternatively or in addition, an ultrasound imaging apparatus configurable for acquiring a 2D, flat image of a curved region within a curved plane includes a transducer array for imaging the region, the array having a face and transducer elements; a module for extracting a centerline of a curved object that contains the curved region; and a processor for: projecting the centerline onto the face of the array; selecting, from among the elements, a set along the projection onto the face; receive beamforming, specifically using the set, to image the curved region and thereby acquire a curved image; and projecting the curved region onto a 2D, flat image plane.

[0036] Although the above discussion is in the context of medical applications, what is proposed herein above is not limited to this area and may, for example, find application in ultrasonic inspection.

[0037] While the invention has been illustrated and described in detail in the drawings and foregoing description, such illustration and description are to be considered illustrative or exemplary and not restrictive; the invention is not limited to the disclosed embodiments.

[0038] For example, instead of a least squares fit optimization of image plane orientation 256, the criterion could depend on the sum of absolute deviations 260.

[0039] Other variations to the disclosed embodiments can be understood and effected by those skilled in the art in practicing the claimed invention, from a study of the drawings, the disclosure, and the appended claims. In the claims, the word “comprising” does not exclude other elements or steps, and the indefinite article “a” or “an” does not exclude a plurality. The word “exemplary” is used herein to mean “serving as an example, instance or illustration.” Any embodiment described as “exemplary” is not necessarily to be construed as preferred or advantageous over other embodiments and/or to exclude the incorporation of features from other embodiments. Any reference signs in the claims should not be construed as limiting the scope.

[0040] A computer program can be stored momentarily, temporarily or for a longer period of time on a suitable computer-readable medium, such as an optical storage medium or a solid-state medium. Such a medium is non-transitory only in the sense of not being a transitory, propagating signal, but includes other forms of computer-readable media such as register memory, processor cache and RAM.

[0041] A single processor or other unit may fulfill the functions of several items recited in the claims. The mere fact that certain measures are recited in mutually different dependent claims does not indicate that a combination of these measures cannot be used to advantage.

1. An ultrasound imaging apparatus configured for acquiring a two-dimensional, flat image of an elongated, curved region disposed within a curved plane, said apparatus comprising:

- an ultrasound transducer array for imaging said curved region that is disposed within said curved plane;
- a localization processor configured for localizing said curved region with respect to said transducer array;
- an image segmentation module configured for segmenting a centerline of an elongated object containing said curved region;
- and
- an ultrasound imaging processor configured for operating said transducer array for said imaging of said curved

region, for determining an optimal orientation of a flat image plane by fitting said flat image plane to the centerline of the elongated object by means of at least square analysis, and for projecting said curved region onto the optimally oriented two-dimensional, flat image plane.

2. (canceled)

3. The apparatus of claim 2, said curved region being a first region, one or more second curved regions being elongated and three-dimensional, said localization processor being further configured for localizing said one or more second curved regions with respect to said transducer array, said imaging processor being further configured for imaging said one or more second regions and for projecting said one or more second curved regions onto said image plane.

4. The apparatus of claim 3, said imaging processor being configured for, by spatially orienting said image plane, fitting said image plane to said region, and to said one or more second regions, in preparation for said projecting of said one or more second curved regions.

5. (canceled)

6. The apparatus of claim 1, further comprising a user interface, said user interface having a display and a user control, said apparatus being further configured for receiving, via said user control, user input for defining said region.

7. The apparatus of claim 6, said imaging processor being configured for said receiving, and for using data received, in said receiving, in deriving a centerline of an elongated object that contains said region.

8. The apparatus of claim 6, further configured for, via said display displaying data outputted by said localizing, the displayed data depicting said region.

9. The apparatus of claim 1, said imaging processor comprising an ultrasound-image-based localization processor configured for said localizing via volumetric ultrasound imaging.

10. The apparatus of claim 1, further comprising a display and configured for, via said display, displaying said image plane.

11. The apparatus of claim 10, further configured for operating said localization processor to dynamically track said elongated object such that said displaying displays said object as a live image (S324-S376).

12. The apparatus of claim 1, said localization processor comprising an electromagnetic tracking system, a shape sensor tracking system, or both an electromagnetic tracking system and a shape sensor tracking system, and being configured for operating the respective one or more of said systems to perform said localizing.

13. The apparatus of claim 1, said region being an object, said apparatus being configured for communicating with one or more structures fixed to said object, said one or more constituting at least one sensor, at least one ultrasound transmitter, or a combination of at least one sensor and at least one ultrasound transmitter.

14. The apparatus of claim 1, said imaging processor comprising a power Doppler imaging module and being configured for said localizing via said power Doppler imaging module.

15. (canceled)

16. (canceled)

17. An ultrasound imaging apparatus configured for acquiring a two-dimensional, flat image of a curved region that is disposed within a curved plane, said apparatus comprising:

an ultrasound transducer array for imaging said curved region that is disposed within said curved plane, said array having a face and a plurality of transducer elements;

an image segmentation module configured for extracting a centerline of a curved object that contains said curved region; and

an ultrasound imaging processor configured for:

projecting the centerline onto said face;

selecting, from among the plural elements, a set along the projection onto said face;

receive beamforming, specifically using said set, to image said curved region and thereby acquire a curved image; and

projecting said curved region onto a two-dimensional, flat image plane.

18. A method for acquiring a two-dimensional, flat image of curved region that is disposed within a curved plane, said method comprising:

localizing, in an acoustic image coordinate frame, said curved region that is disposed within said curved plane;

segmenting a centerline of an elongated object containing said curved region;

determining an optimal orientation of a flat image plane by fitting said flat image plane to the centerline of the elongated object by means of a least square analysis; and

projecting said curved region onto a the optimally oriented two-dimensional, flat image plane.

19. A computer-readable medium embodying a program for acquiring a two-dimensional, flat image of curved region that is disposed within a curved plane, said program having instructions executable by a processor for performing a plurality of acts, from among said plurality there being the acts of:

localizing, in an acoustic image coordinate frame, said curved region that is disposed within said curved plane;

segmenting a centerline of an elongated object containing said curved region;

determining an optimal orientation of a flat image plane by fitting said flat image plane to the centerline of the elongated object by means of a least square analysis,

and

projecting said curved region onto a the optimally oriented two-dimensional, flat image plane (S360).

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摘要(译)

超声成像设备可配置用于获取弯曲平面内的弯曲区域 (206) 的二维平面图像。该装置包括用于对该区域成像的换能器阵列;用于相对于换能器阵列定位该区域的处理器;以及处理器, 用于操作换能器阵列以对该区域进行成像并将该区域投影到二维 (2D) 平面图像平面上。替代地或另外地, 可配置用于获取弯曲平面内的弯曲区域的2D平面图像的超声成像设备包括用于对该区域成像的换能器阵列, 该阵列具有面和换能器元件 (142);用于提取包含弯曲区域的弯曲物体的中心线的模块;和处理器: 用于: 将中心线 (254) 投影到阵列的面上;从元素中选择沿投影到面部的一组;接收波束成形, 特别是使用该集合, 对弯曲区域进行成像, 从而获得弯曲图像;并将弯曲区域投影到2D平面图像平面上。

