

Direct Co-Calibration of Endobronchial Ultrasound and Video

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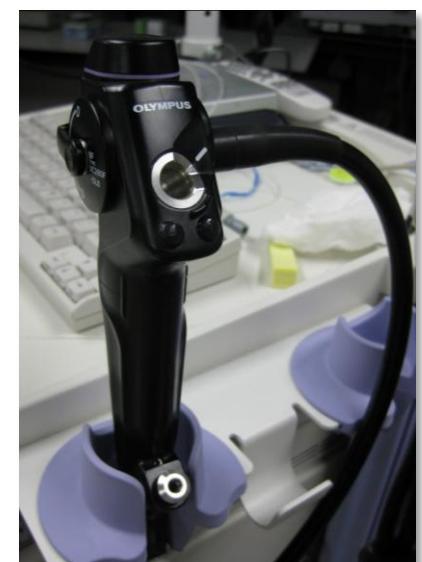
³Faculty of Information Science, Aichi Institute of Technology, Japan

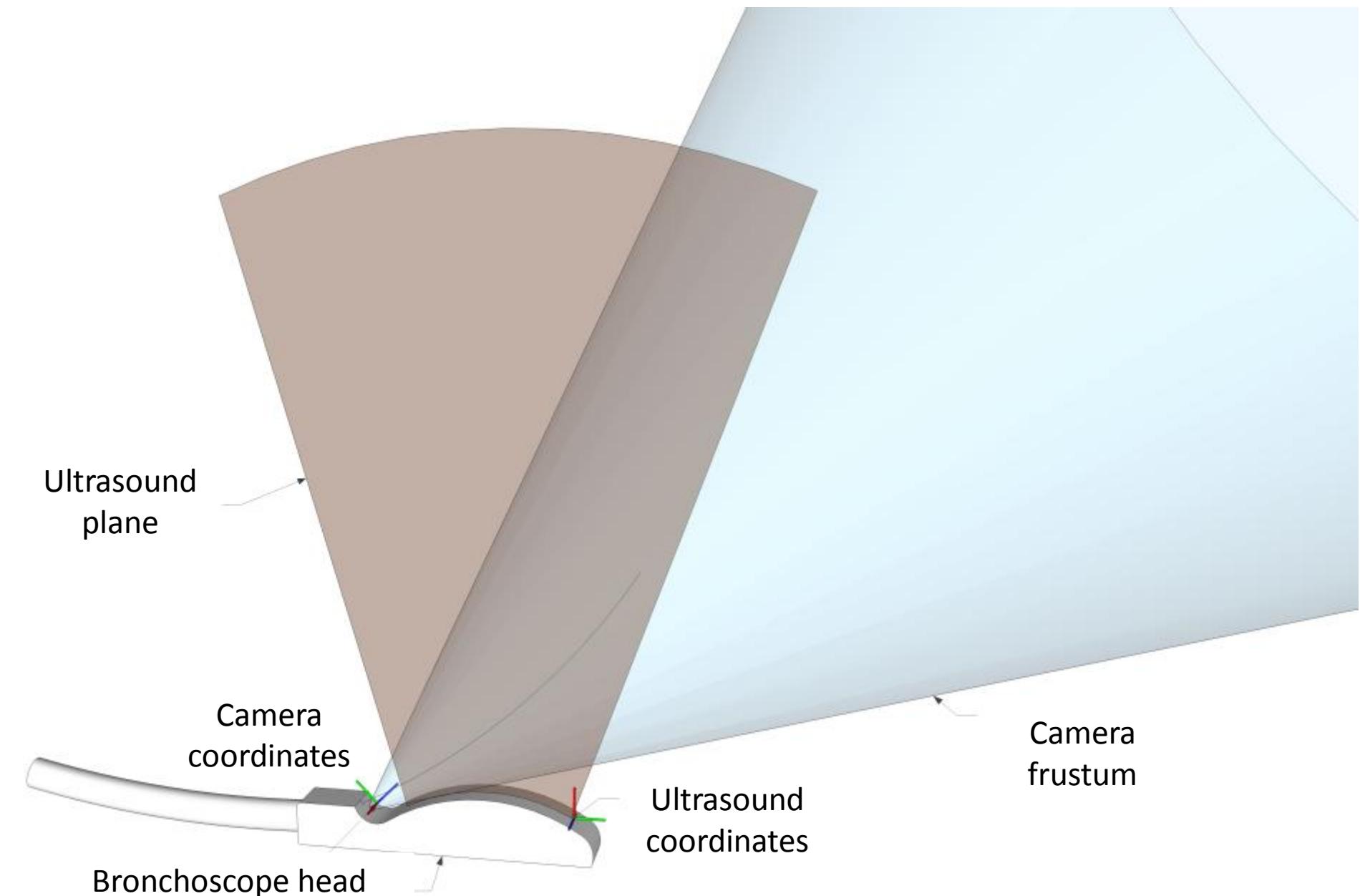
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Introduction



- Endobronchial ultrasound (EBUS)
- Navigation solutions may require US/Cam calibration

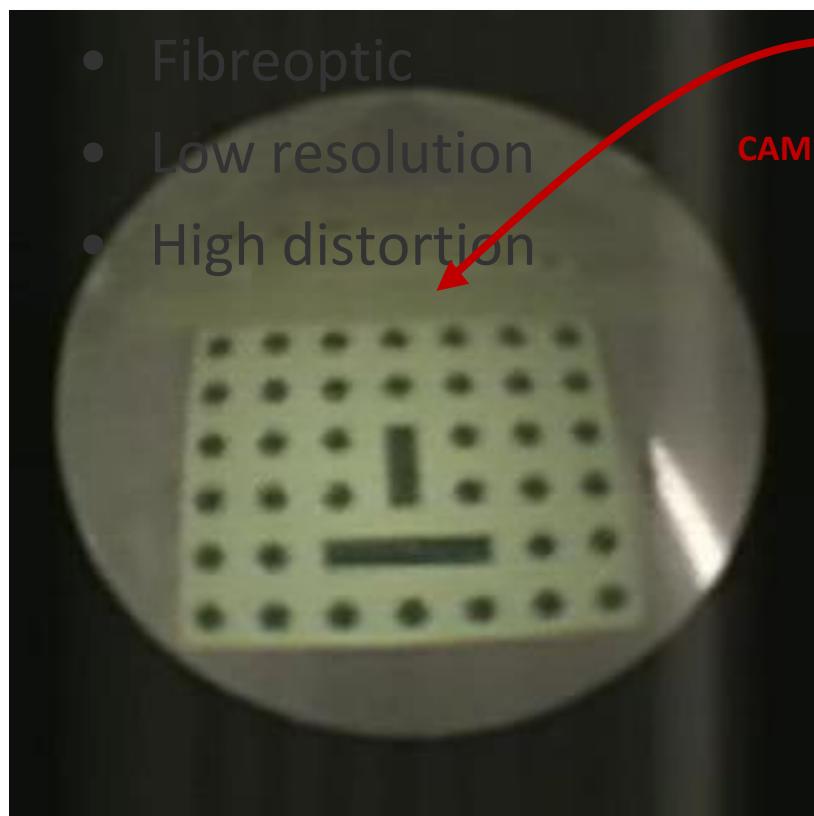




Introduction

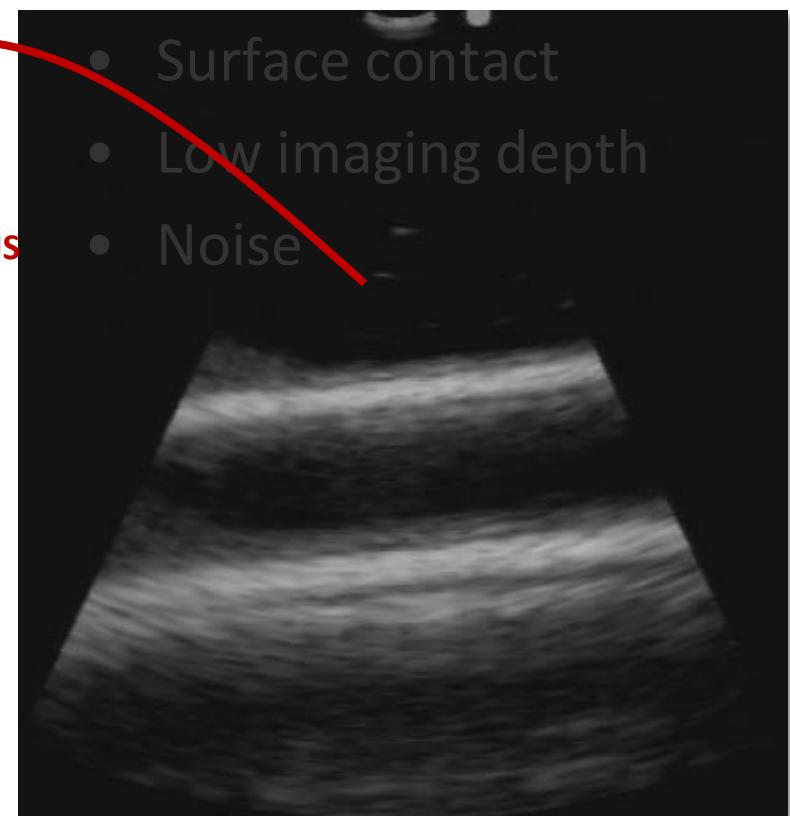
Camera

- Fibreoptic
- Low resolution
- High distortion



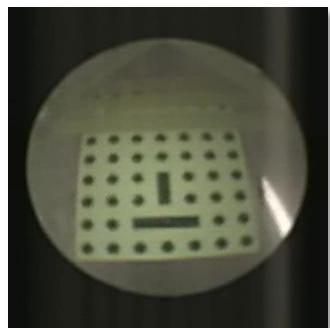
Ultrasound

- Surface contact
- Low imaging depth
- Noise



Method

$$\lambda \cdot \begin{pmatrix} x \\ y \\ 1 \end{pmatrix} = [K \mid 0] \cdot {}^{CAM}H_{US} \cdot \begin{pmatrix} u \cdot s_u \\ v \cdot s_v \\ 0 \\ 1 \end{pmatrix}$$



- | | |
|--------------|------------------------------|
| λ | Image scaling |
| (x, y) | Camera image coordinates |
| K | Camera matrix |
| (u, v) | Ultrasound image coordinates |
| (s_u, s_v) | Ultrasound scaling |

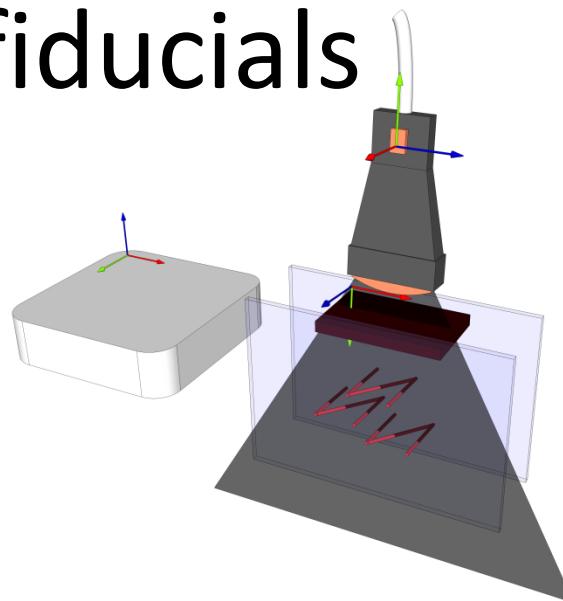
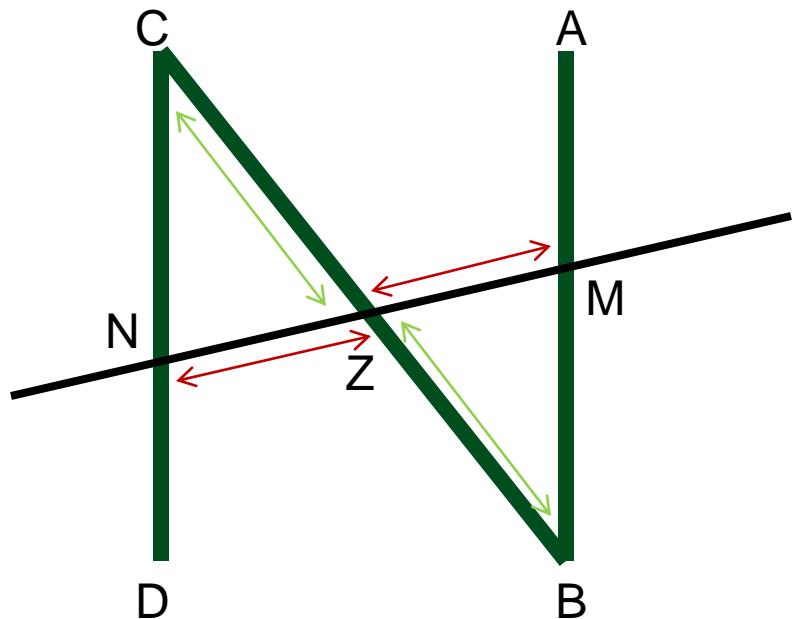
Method

- Measure phantom in advance
→ Allows calibration from single image pair
- Estimate camera pose using method of Wengert
(also considering distortion and adjusting for velocity in water
with refractive index 1.33)
- Estimate ultrasound pose using Z-fiducial method
- Combine series of images for increased accuracy

$$\lambda \cdot \begin{pmatrix} x \\ y \\ 1 \end{pmatrix} = [K \mid 0] \cdot {}^{CAM}H_P \cdot {}^P H_{US} \cdot \begin{pmatrix} u \cdot s_u \\ v \cdot s_v \\ 0 \\ 1 \end{pmatrix}$$

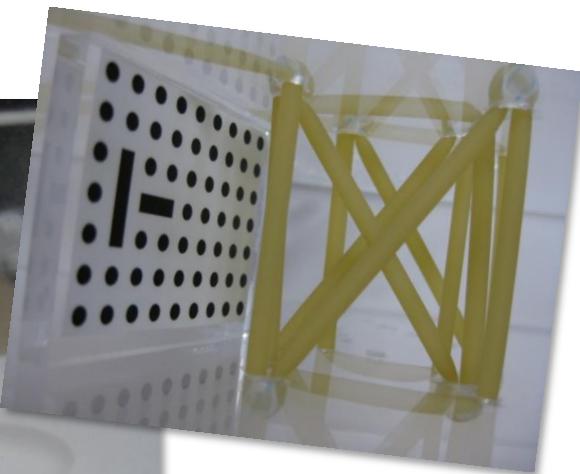
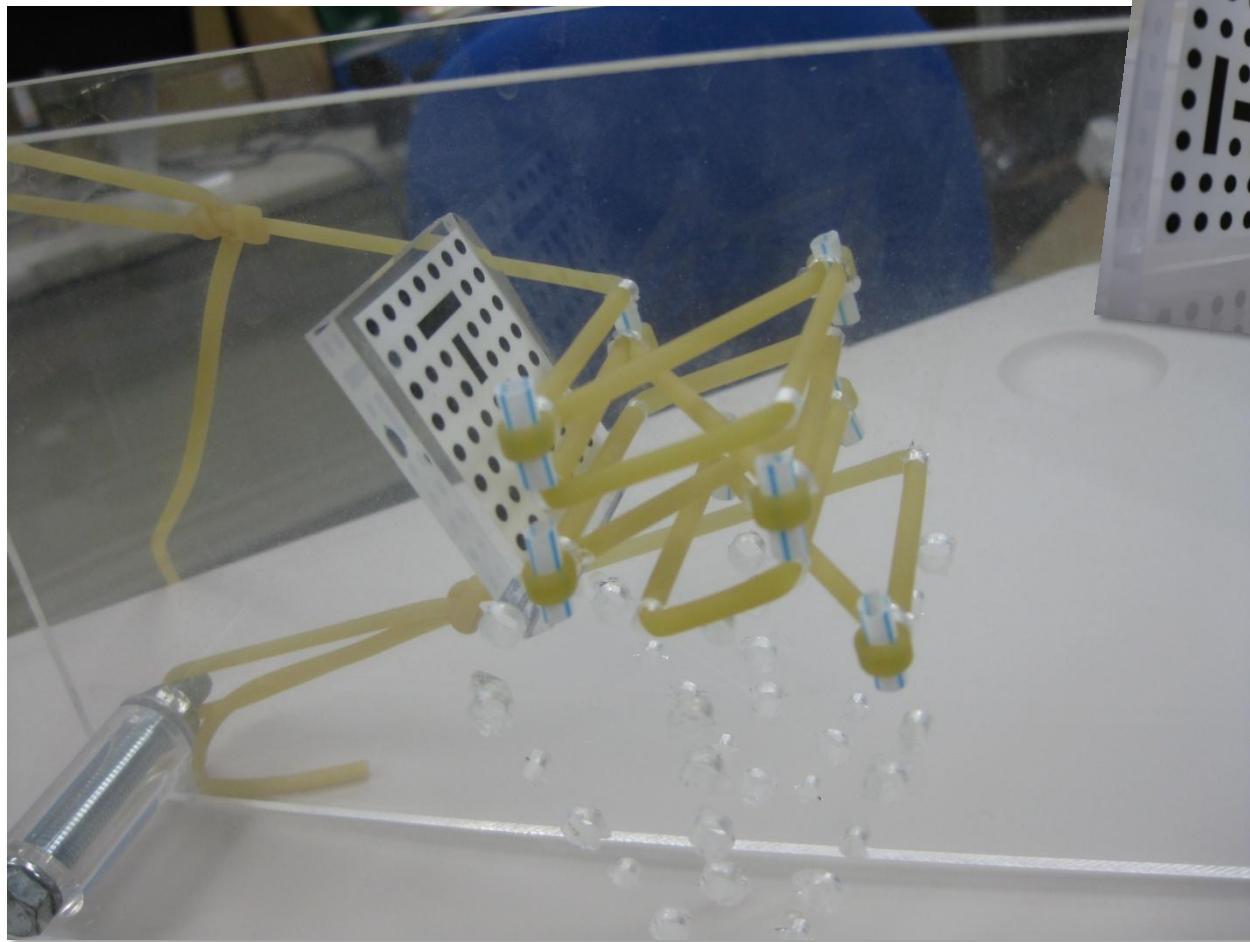
Method: Z-fiducials

$$Z = B + \frac{|\overline{BZ}|}{|\overline{BC}|}(C - B) = B + \frac{|\overline{MZ}|}{|\overline{MN}|}(C - B)$$



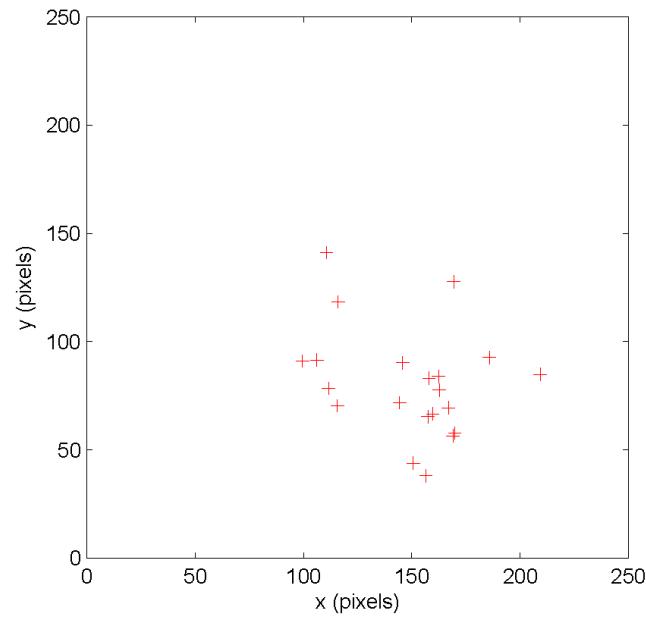
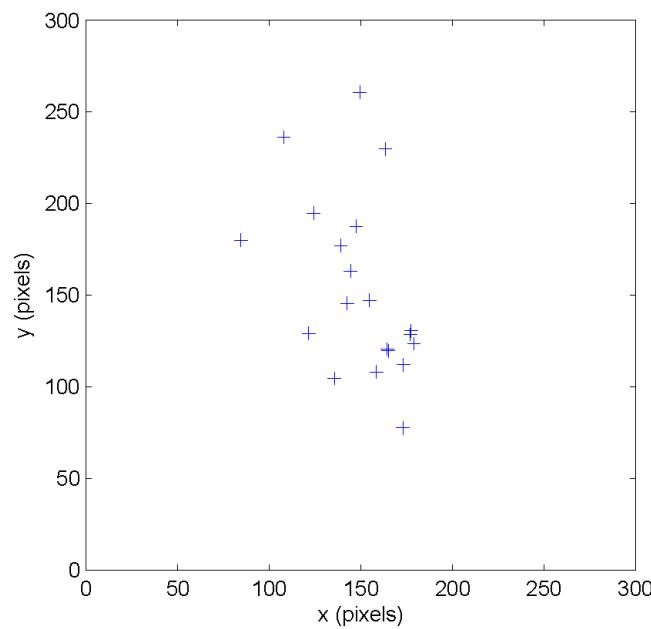
Method: [Hsu, P., Prager, R., Gee, A., Treece, G.: Real-time freehand 3D ultrasound calibration. Ultrasound in Medicine & Biology 34(2) (2008) 239-251]

Phantom



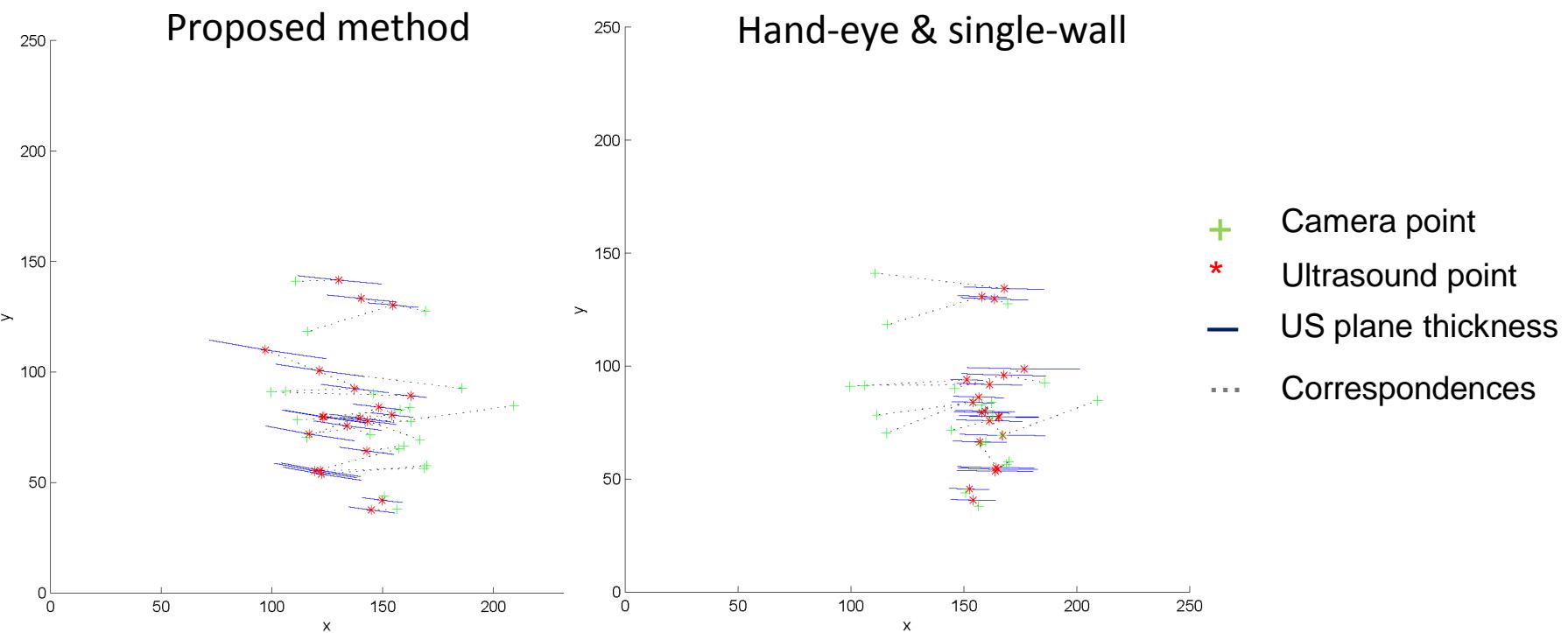
Results

- Use tool tip to mark corresponding locations
- Move until tip is visible in ultrasound



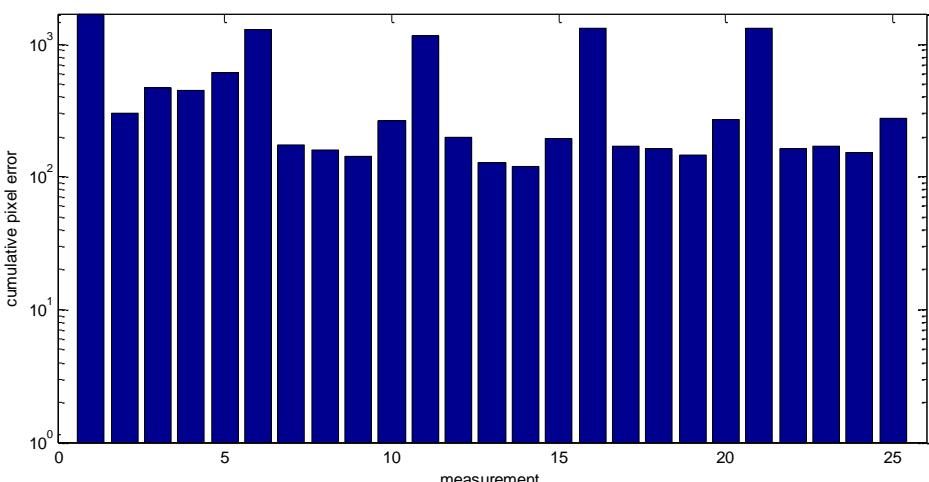
Results

- Sample point locations
- Compute cumulative pixel distance of point pairs

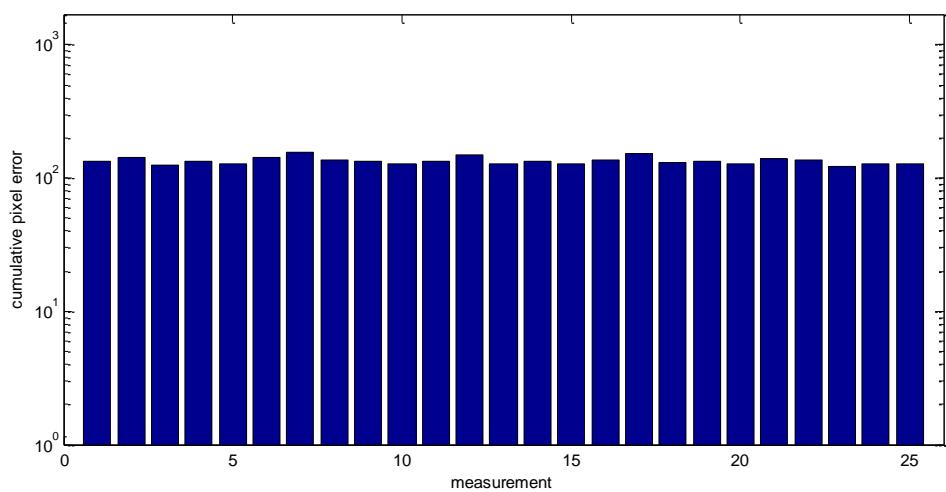


Results

Hand-eye & single-wall



Proposed method



$$cpe = \sum_{i=1}^n |p_y^i - q_y^i|$$

Conclusion

- Compared to hand-eye and single-wall:
 - Comparable accuracy
 - Higher precision
 - Faster
 - Build more complex phantom once
 - Calibrate quickly many times