

Three-dimensional image registration

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Three-dimensional image registration

- Introduction
- Registration Methods
- Transform
- Diagram
- Results
- Future work
- Reference
- Questions

Introduction

What is Registration?

- The process of finding the transformation that constitutes the best alignment between images. Ex. Images acquired of the same patient at different times (head position).

Why do registration?

- The need occurs when the images have to be processed, and the algorithm assumes that the images are aligned. Ex. Merge images.

Registration Methods

i. Manual methods

- User does all the alignment and the computer provides only the visual feedback

ii. External Landmark Registration

- Oil markers are placed on patient before image acquisition.
- Two steps: 1. Identify at least three pairs of corresponding points; 2. Calculate the transformation using the corresponding points;

Registration Methods

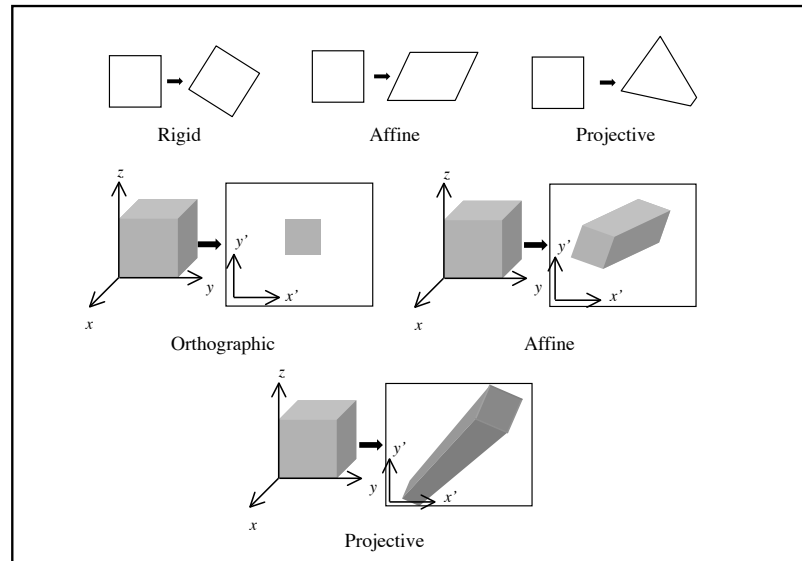
iii. Voxel intensity-based

- Metric - Ex. Normalized Mutual Information;
- Optimization method - Ex. Extensive direction - Ramp;
- Transformation model - Ex. Rigid-body transform;

Data	Data	Reg.	obs
MRI	CT	M/EL	-
MRI	MR	M/EL/VI	-

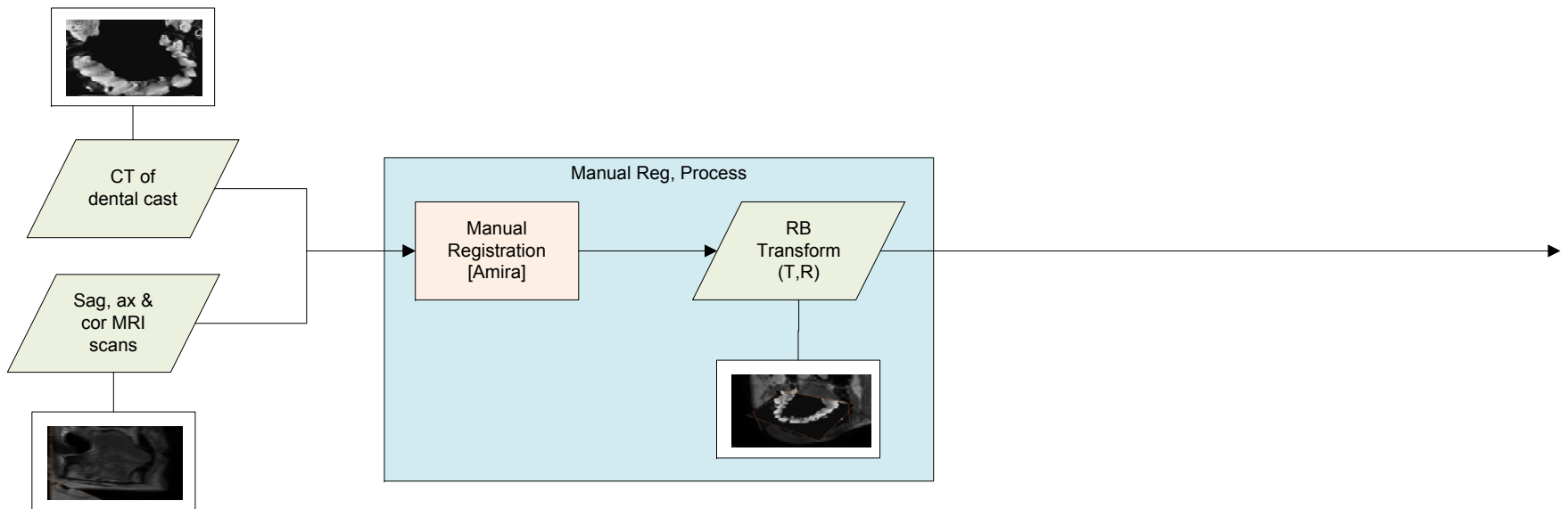
Transform

	Reflection	Translation	Rotation	Scaling	Projection	Curves
Rigid	X	X	X			
Affine	X	X	X	X		
Projective	X	X	X	X	X	
Curved	X	X	X	X	X	X



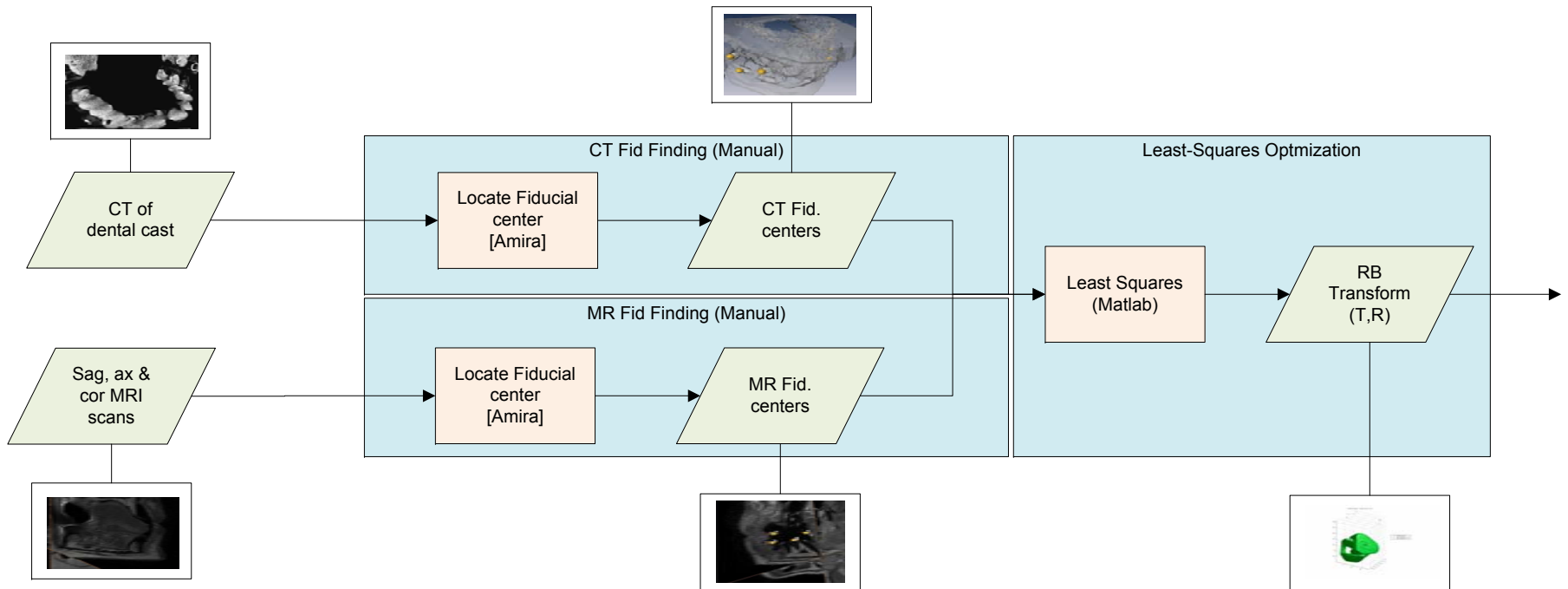
Registration Methods - Diagram

i. Manual methods

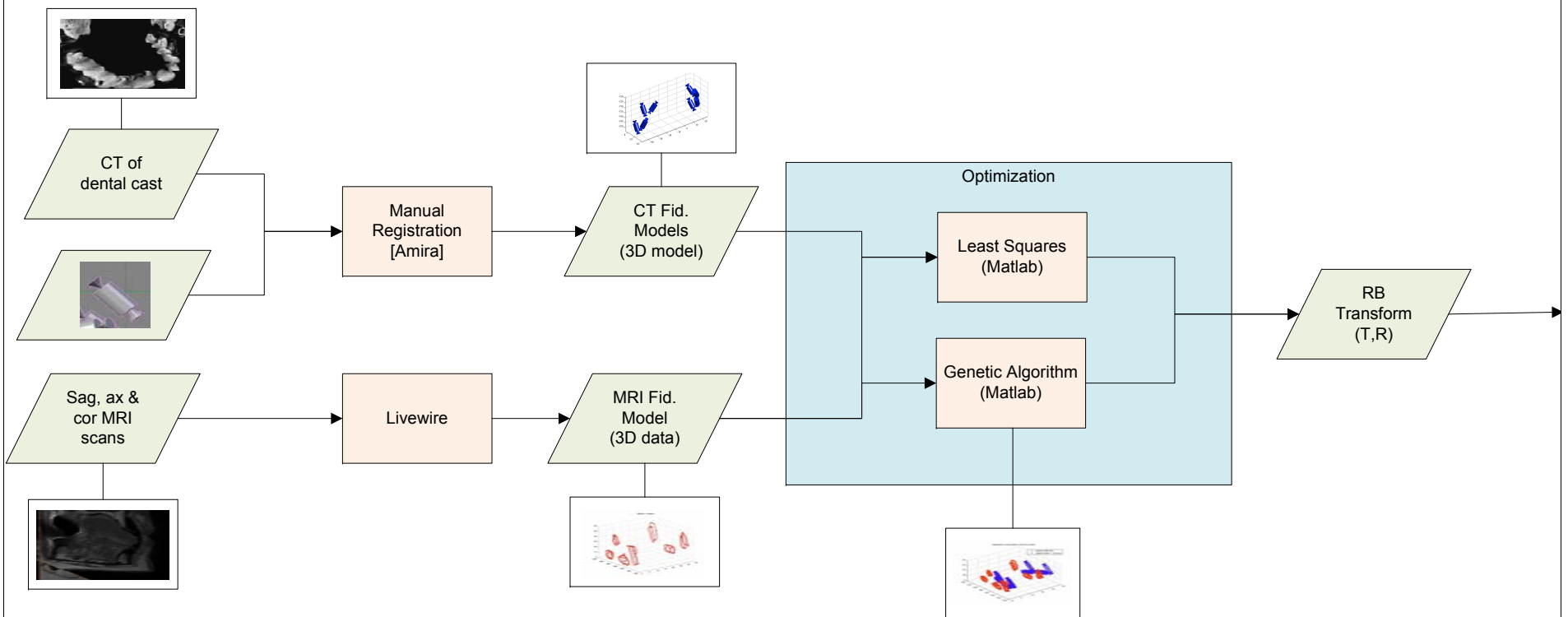


Registration Methods - Diagram

ii. External Landmark Registration

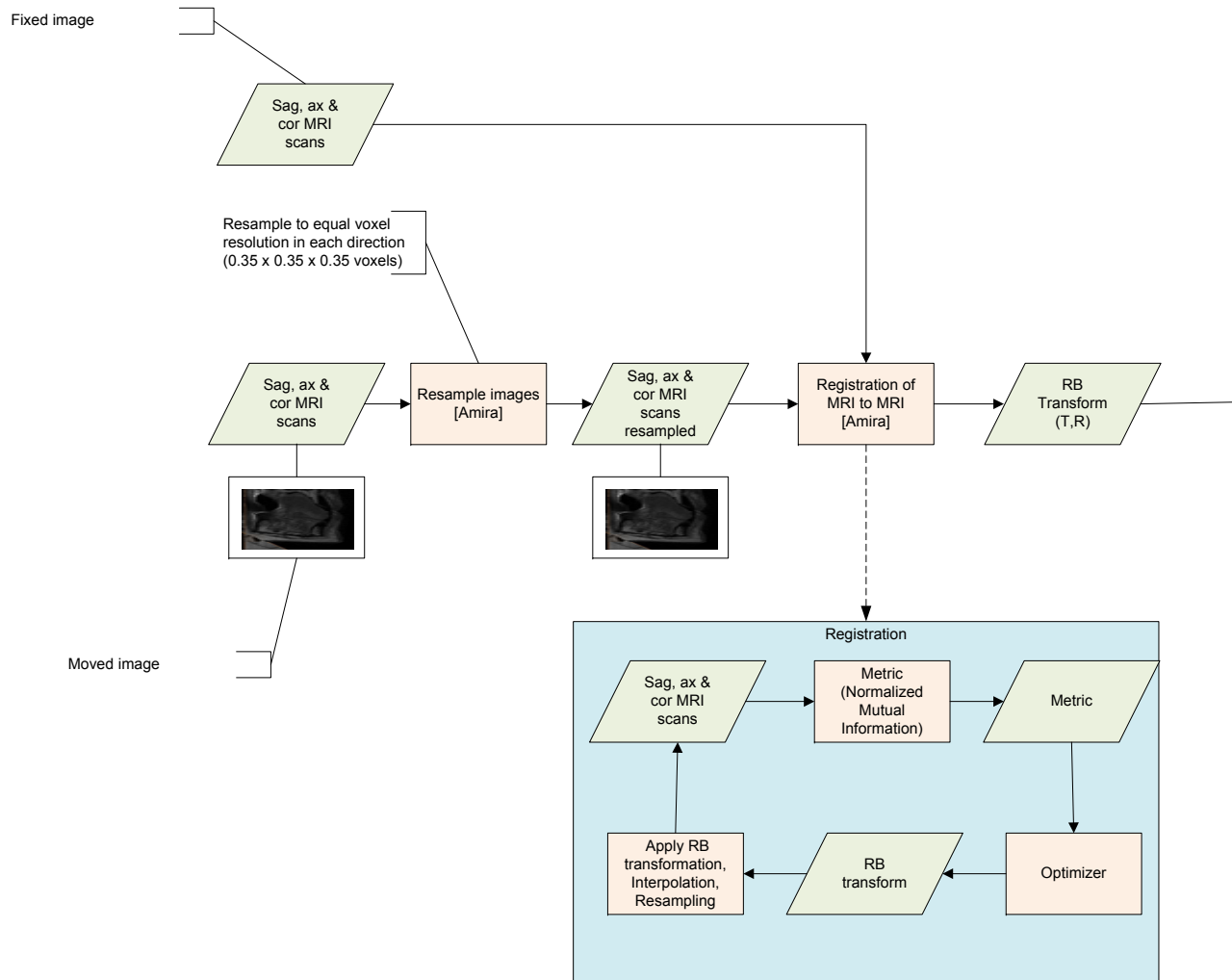


Registration Methods - Diagram

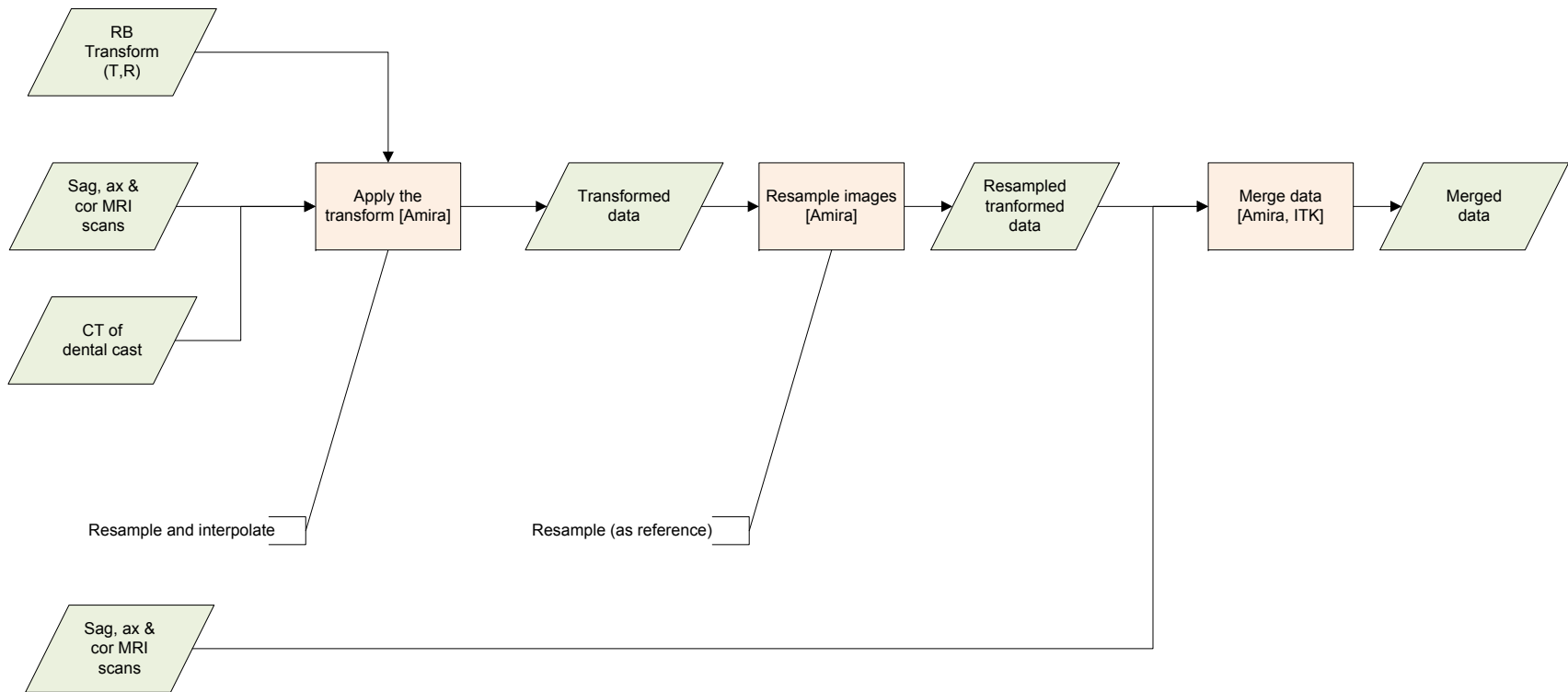


Registration Methods - Diagram

iii. Voxel intensity-based



Merge data - Diagram



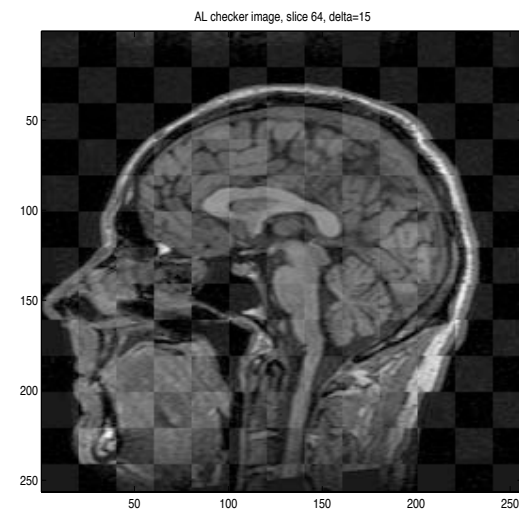
Result

CT and MR merged Data

MR merged Data

Future Work

- Implement Template Matching to detect the markers in MR and CT scans
- Implement the Checkerboard to visual validation (MR registration)



Questions

Questions?

Comments?

References

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[2] Black, Kevin John and Videen, Tom O. and Perlmutter, Joe S. *A metric for Testing the Accuracy of Cross-Modality Image Registration: Validation and Application*. *Journal of Computer Assisted Tomography*, 855 861, 1996.

[3] Shinji Umeyama. "Least-Squares Estimation of Transformation Parameters Between Two Point Patterns." *IEEE Transactions on Pattern Analysis and Machine Intelligence*. Vol 13, No. 4, April 1991."

References

[4] Kaneko et al., 2003. "Robust matching of 3D contours using iterative closest point algorithm improved by M-estimation". Journal of the Pattern Recognition Society. v36. 2041-2047.

[5] Chetverikov et al., 2005. "Robust Euclidean alignment of 3D point sets: the trimmed iterative closest point algorithm". Image and Vision Computing. v23. 299-309.