NSF Engineering Research Center
for Computer Integrated Surgical
Systems and Technology

LABORATORY FOR
Computational
Sensing + Robotics
THE JOHNS HOPKINS UNIVERSITY

Notes for PA5: Deformable Registration to a Statistical Shape Model

100 YEARS
JOHNS HOPKINS ENGINEERING

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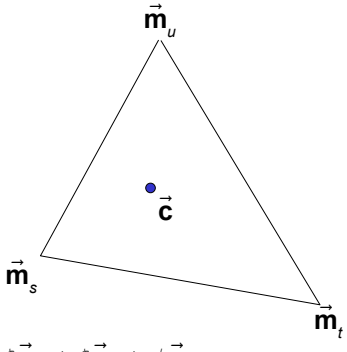
Barycentric Coordinates of Deforming Triangle



$$\vec{c} = \zeta\vec{m}_s + \xi\vec{m}_t + \psi\vec{m}_u$$

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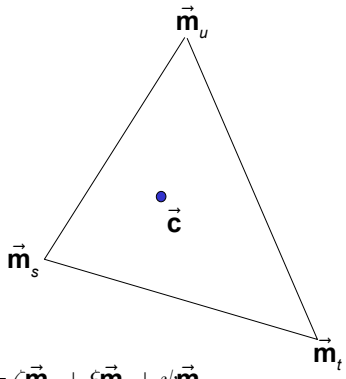
Barycentric Coordinates of Deforming Triangle



$$\vec{c} = \zeta\vec{m}_s + \xi\vec{m}_t + \psi\vec{m}_u$$

$$\vec{m}_s = \vec{m}_{0,s} + \sum_{m=1}^{Nmodes} \lambda_m^{(t)}\vec{m}_{m,s}$$

$$\vec{m}_t = \vec{m}_{0,t} + \sum_{m=1}^{Nmodes} \lambda_m^{(t)}\vec{m}_{m,t}$$

$$\vec{m}_u = \vec{m}_{0,u} + \sum_{m=1}^{Nmodes} \lambda_m^{(t)}\vec{m}_{m,u}$$

$$\vec{q}_{m,k} = \zeta_k\vec{m}_{m,s} + \xi_k\vec{m}_{m,t} + \psi_k\vec{m}_{m,u}$$

$$\vec{c}_k^{(t)} = \vec{q}_{0,k} + \sum_{m=1}^{N_{modes}} \lambda_m^{(t)}\vec{q}_{m,k}$$

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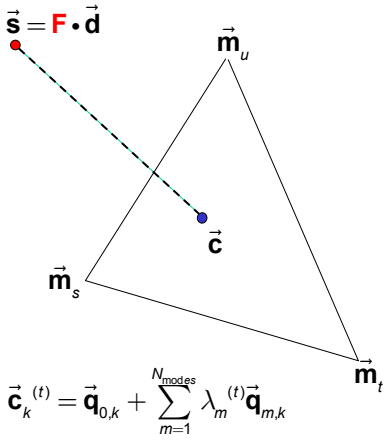
Deformable Registration to SSM



$$\vec{c}_k^{(t)} = \vec{q}_{0,k} + \sum_{m=1}^{N_{modes}} \lambda_m^{(t)}\vec{q}_{m,k}$$

Step 1 For sample points, find closest matches to current mesh

Step 2 Solve $\mathbf{F} \bullet \vec{d}_k \approx \vec{q}_{0,k} + \sum_{m=1}^{N_{modes}} \lambda_m^{(t)}\vec{q}_{m,k}$ for $\mathbf{F}$ and/or $\lambda_m^{(t)}$

Step 3 If change the shape parameters then update bounding boxes

Step 4 Iterate to convergence

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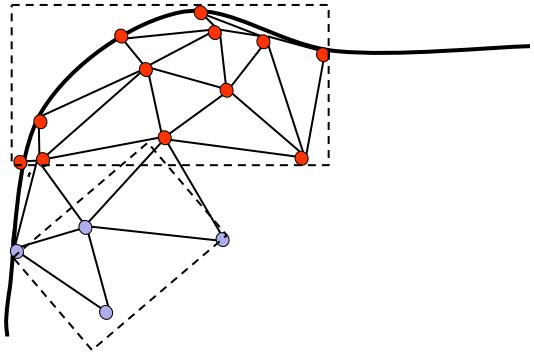
Updating Bounding Boxes



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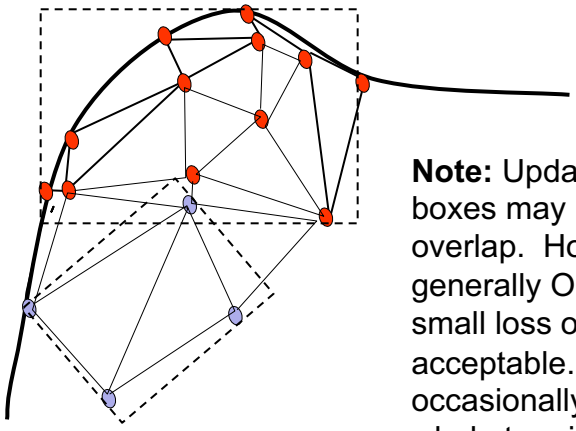
Updating Bounding Boxes



Note: Updated bounding boxes may increase overlap. However, this is generally OK, since some small loss of efficiency is acceptable. You can occasionally rebuild the whole tree if it becomes an issue.

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