Inverse problems and machine learning in medical physics
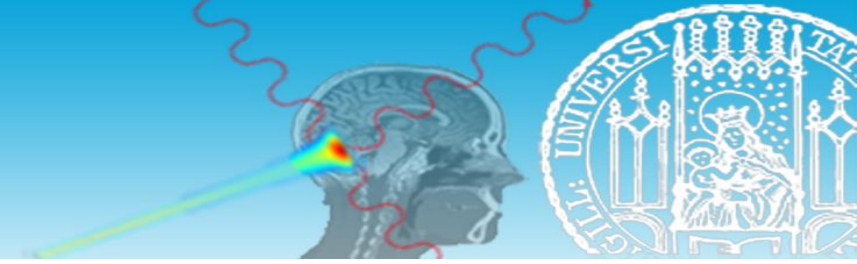
Robotics in radiation therapy

Dr. Chiara Gianoli

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chiara.gianoli@physik.uni-muenchen.de
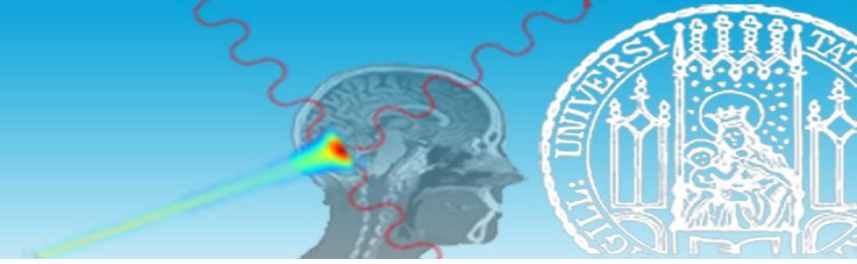
The CyberKnife

- The CyberKnife is a radiation delivery system that features a linear accelerator (*linac*) directly mounted on a robot to deliver photons for radiation therapy, a fluoroscopic kV X-ray imaging for pre-treatment and intra-treatment image-guidance and an optical system for respiratory motion tracking

  - 3D conformal radiotherapy (3D-CRT), including intensity modulated radiation therapy (IMRT)

  - Stereotactic radiosurgery (SRS) and stereotactic body radiation therapy (SBRT) treatments
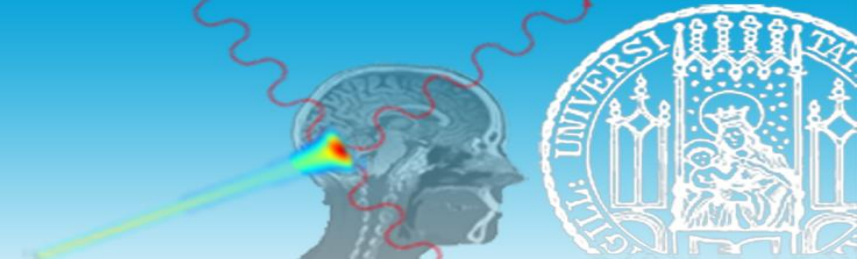
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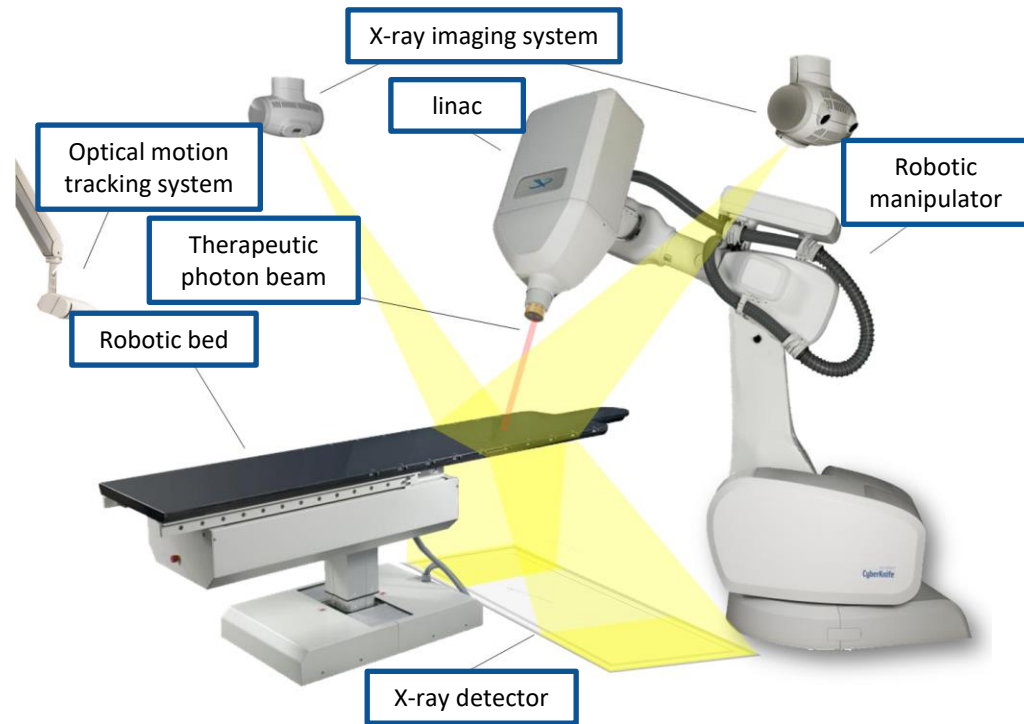
- The beams are delivered from fixed points in space called nodes, arranged in spherical (intracranial applications) or ellipsoidal (extracranial applications) configurations

- The combination of nodes and pointing vectors (twelve for each node) provides a set of "elementary beams" to plan the treatment
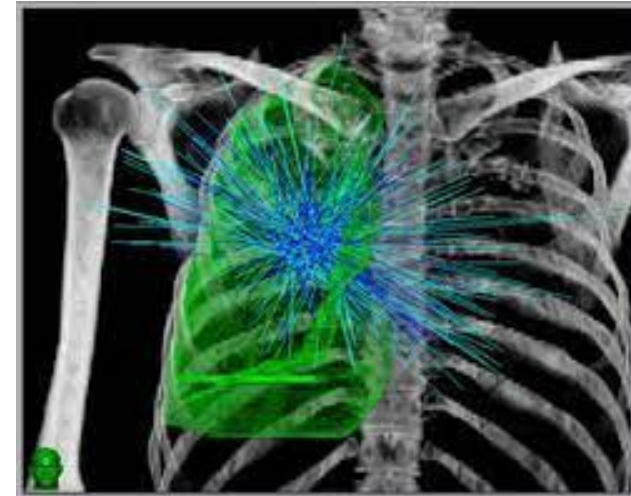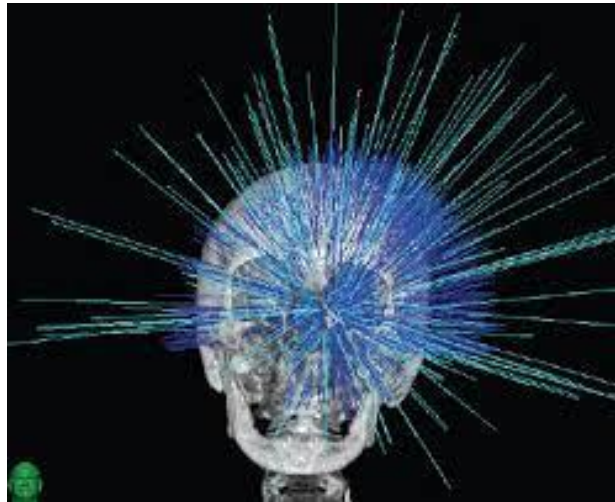
- Prior to the treatment, eight radiographic X-ray images in different breathing phases are compared to the DRRs of the treatment planning X-ray CT image to determine by triangulation the transformation to be applied to the 6-DoF robotic bed for patient positioning
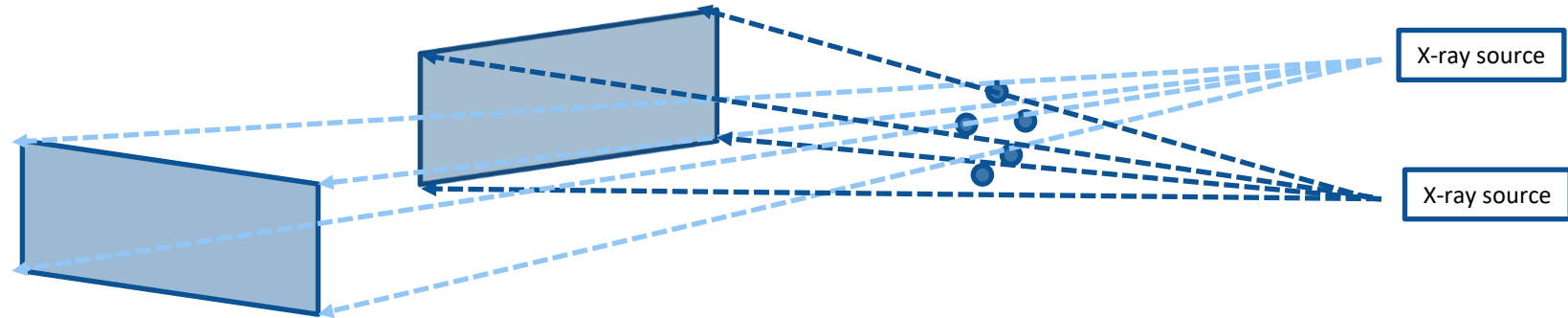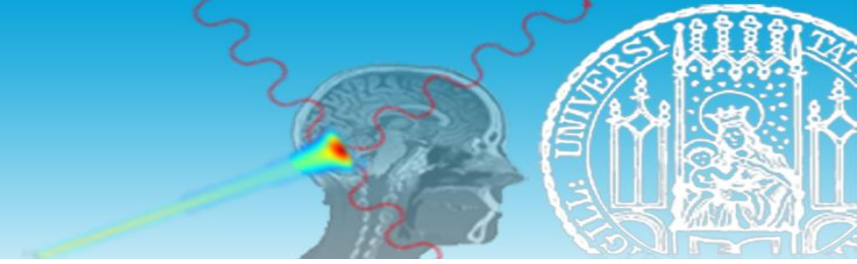

- During the treatment, this transformation is adjusted in real-time by moving the end-effector of the 6-DoF robotic manipulator (*linac*) according to the moving target

- The motion tracking considers:

  - Fiducial-free tumor tracking based on the optical tracking system (for external localization at 20–40 Hz) and implanted radio-opaque markers near or inside the tumor based on the X-ray imaging system (for internal localization every 30s) thus making use of external-internal correlation models

    - The model is constructed in ~30s at the beginning of the treatment and enables motion prediction for delay compensation (~ms)
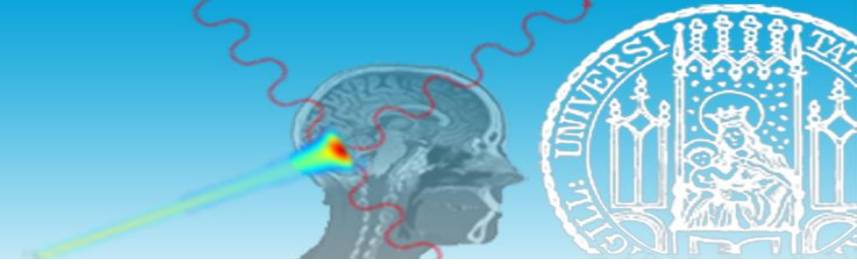
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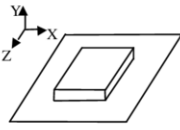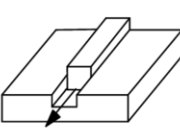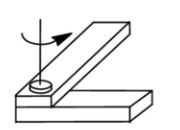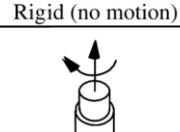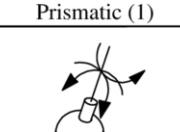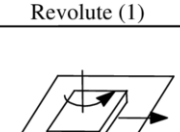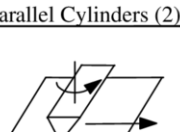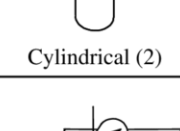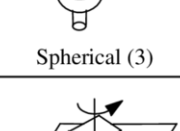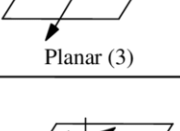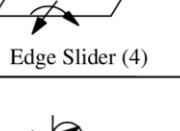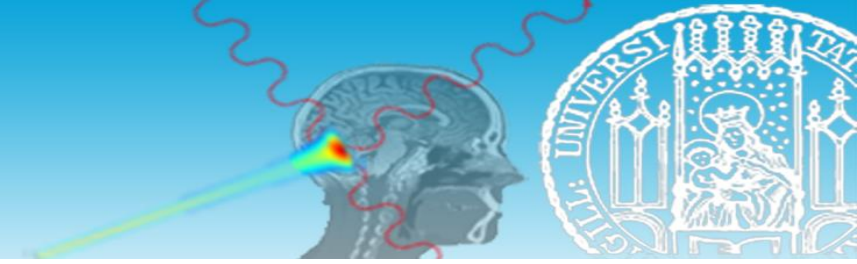
- *First of all, we have to know where the robot is...*

- Kinematics is the science of motion that treats motion without regard to the forces which cause it (i.e., position, velocity, acceleration...)

- The forward kinematics problem is about the knowledge of the position of the end-effector, given the kinematic chain of the mechanical system

  - The kinematic chain is an assembly of links (rigid bodies) connected by joints providing degrees of freedom (DoF) to the end-effector

  - the number of DoF of the end-effector is determined by the DoF of all the joints (i.e., 1-DoF for each revolute joint)

- The kinematic chain is described by the joint variables (i.e., the angles for the revolute joints)

- In order to unequivocally localize the position of the end-effector in function of the angles of the kinematic chain (joints and links), the Denavit–Hartenberg convention (D-H convention) is commonly adopted

    - The n links are numbered from 0 (the base of the kinematic chain) to n-1 (the end-effector)
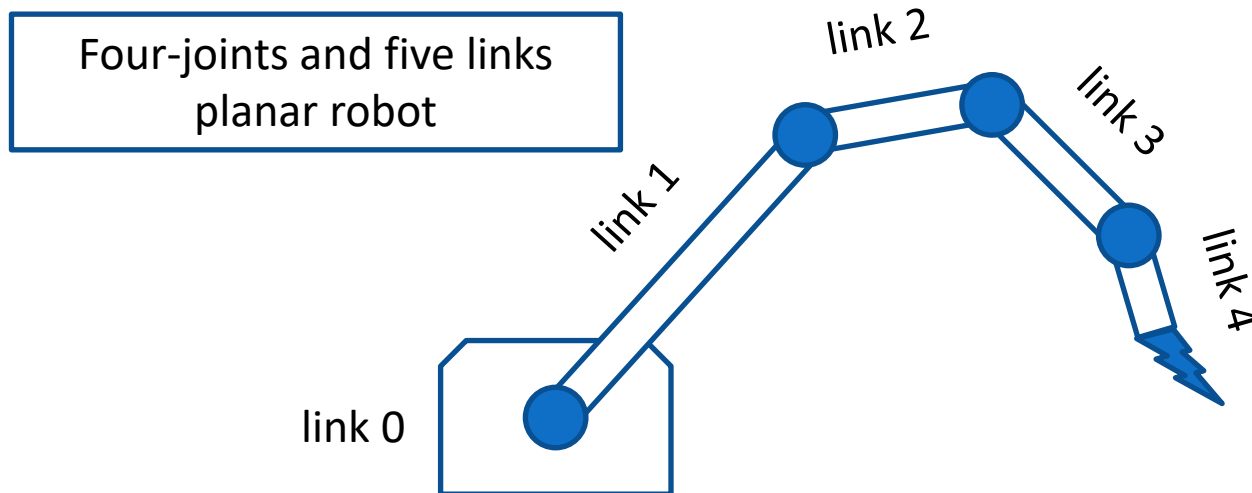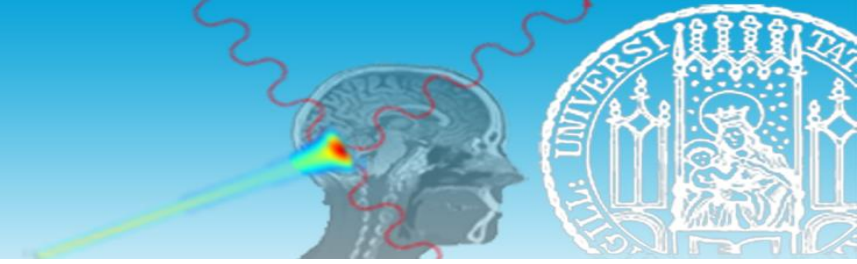
Four-joints and five links planar robot

- In order to unequivocally localize the position of the end-effector in function of the angles of the kinematic chain (joints and links), the Denavit–Hartenberg convention (D-H convention) is commonly adopted

    - The *n-1* joints are numbered from 1 to *n-1* so that the joint *n* connects the link *n-1* (the base of the kinematic chain) to the link *n* (the end-effector)
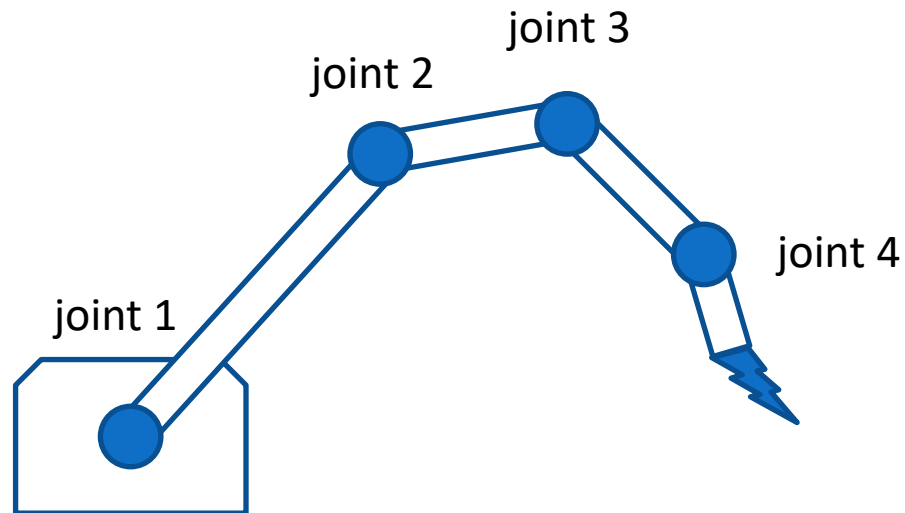
- In order to unequivocally localize the position of the end-effector in function of the angles of the kinematic chain (joints and links), the Denavit–Hartenberg convention (D-H convention) is commonly adopted

  - A frame *n* is defined at the joint n
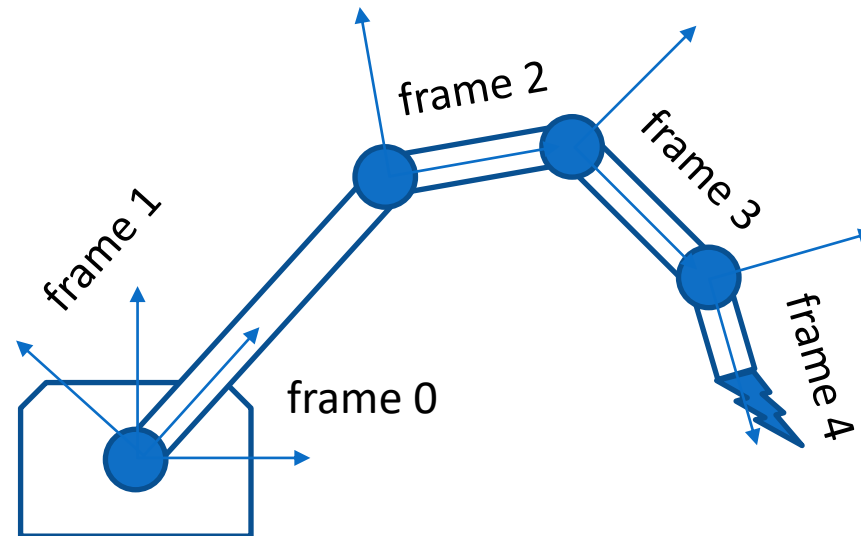
- Z_n is defined as the rotational axis of the revolute joint n

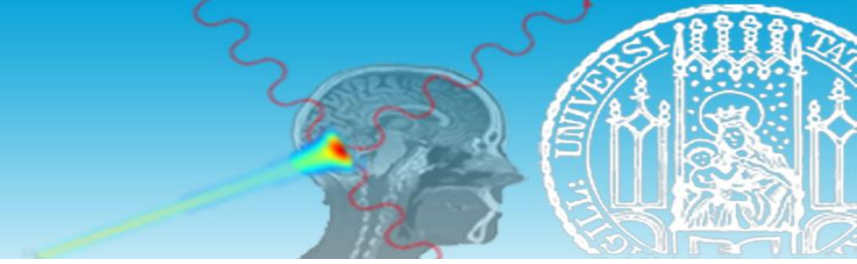 - If Z_n and Z_{n+1} are skew lines, X_n is defined along the common perpendicular of Z_n and Z_{n+1} (the shortest distance between two skew lines is the distance between their intersection points with their common perpendicular), from Z_n to Z_{n+1}

  - The origin of the frame n is defined at the intersection point with Z_n

  - Y_n is defined according to the right-hand frame
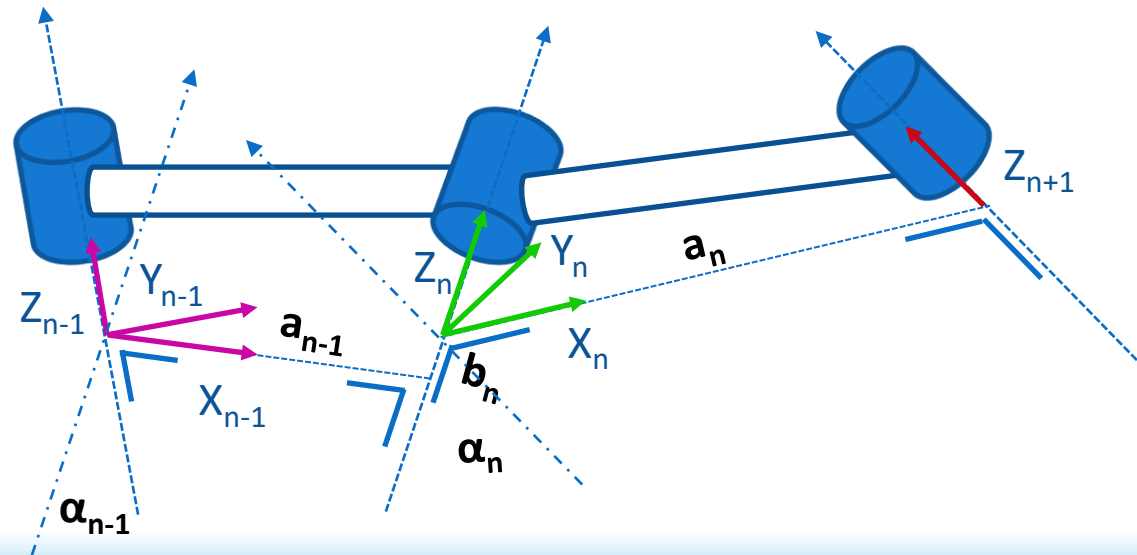
- Z_n is defined as the rotational axis of the revolute joint n

  - If Z_n and Z_{n+1} are parallel lines (i.e., planar robot), X_n is defined along the common normal of Z_n and Z_{n+1}, from Z_n to Z_{n+1}

  - The origin of the frame n is set on the joint n

  - Y_n is defined according to the right-hand frame
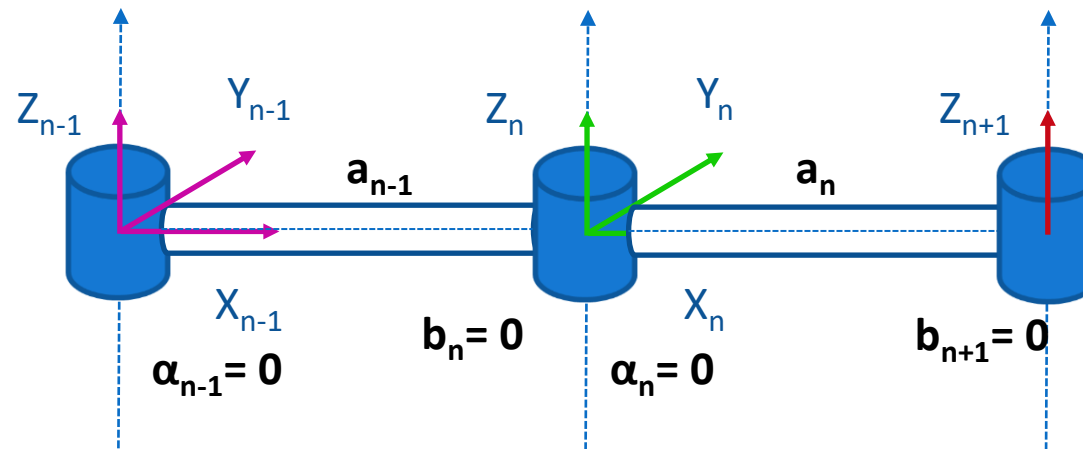
- Z_n is defined as the rotational axis of the revolute joint n

    - If Z_n and Z_{n+1} are intersecting lines, X_n is defined by the vector product between Z_n and Z_{n+1} (i.e., according to the right-hand frame)

    - The origin of the frame n is set on the intersection point

    - Y_n is defined according to the right-hand frame
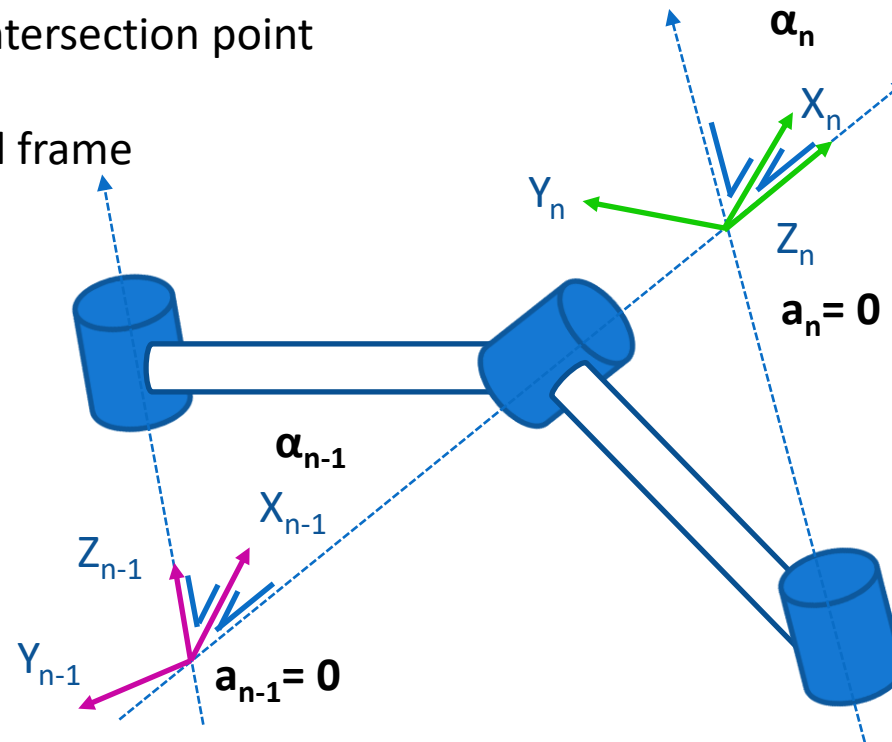
α_n

X_n

Y_n

Z_n

$a_n = 0$

α_{n-1}

X_{n-1}

Z_{n-1}

Y_{n-1}

$a_{n-1} = 0$

- Based on this convention, four Denavit–Hartenberg parameters (D-H parameters) are defined for each joint

  - **I D-H parameter a_n** (link length)

    - a_n is the absolute distance between Z_n and Z_{n+1}

  - **II D-H parameter b_n** (joint offset)

    - b_n is the distance along Z_n between X_{n-1} and X_n

  - **III D-H parameter α_n** (twist angle)

    - α_n is the angle between Z_n and Z_{n+1} across X_n (positive if counterclockwise)

  - **IV D-H parameter ϑ_n** (joint angle)

    - ϑ_n is the angle between X_{n-1} and X_n across Z_{n-1} (positive if counterclockwise)

- Based on this convention, four Denavit–Hartenberg parameters (D-H parameters) are defined for each joint

- The forward kinematics describe the transformation of the frame n with respect to the frame n-1 as a composition of rotations and translations in the Denavit-Hartenberg matrix (D-H matrix)

$$^{n-1}_{n}T = R_X(\boldsymbol{\alpha_{n-1}})D_X(\boldsymbol{a_{n-1}})R_Z(\boldsymbol{\vartheta_n})D_Z(\boldsymbol{b_n})$$

- Translation along Z_n equal to $\boldsymbol{b_n}$
- Rotation across Z_n equal to $\boldsymbol{\vartheta_n}$
- Translation along X_{n-1} equal to $\boldsymbol{a_{n-1}}$
- Rotation across X_{n-1} equal to $\boldsymbol{\alpha_{n-1}}$
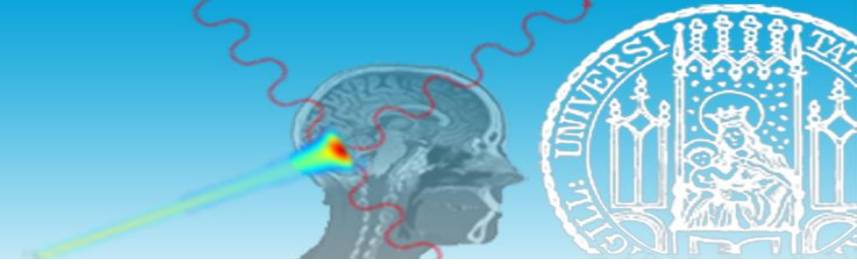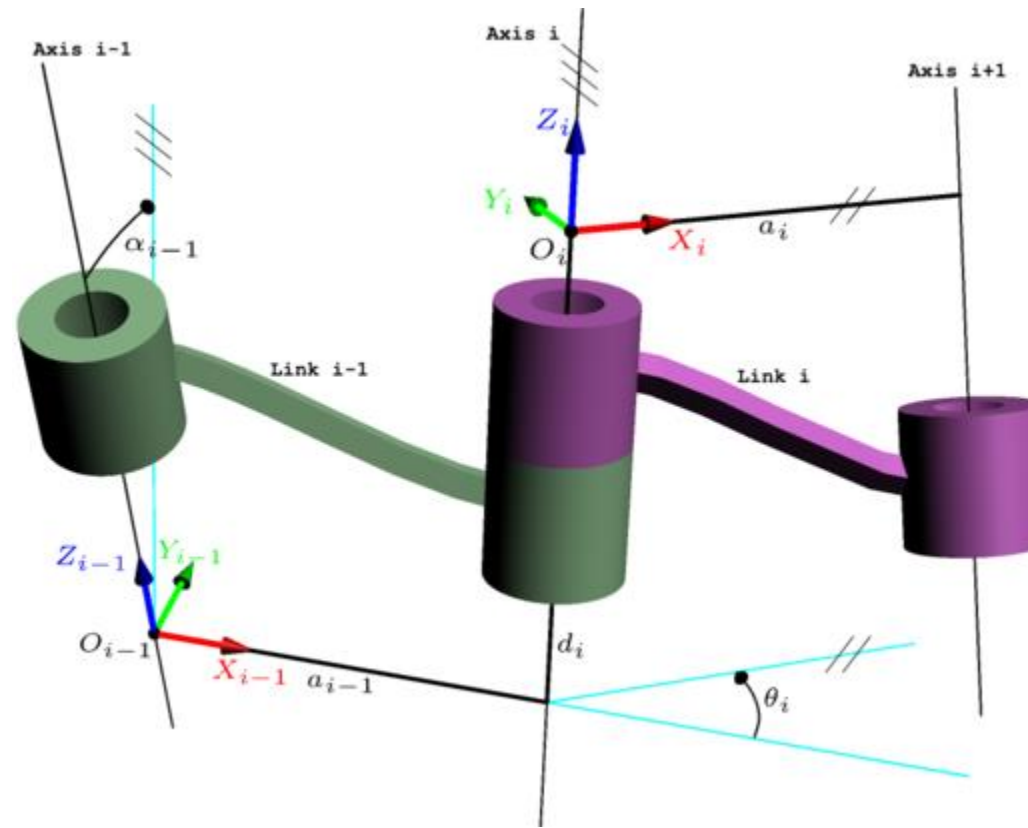
$$^{n-1}_{n}T = \begin{bmatrix} cos(\boldsymbol{\vartheta_n}) & -sin(\boldsymbol{\vartheta_n}) & 0 & \boldsymbol{\alpha_{n-1}} \\ sin(\boldsymbol{\vartheta_n})cos(\boldsymbol{\alpha_{n-1}}) & cos(\boldsymbol{\vartheta_n})cos(\boldsymbol{\alpha_{n-1}}) & -sin(\boldsymbol{\alpha_{n-1}}) & -sin(\boldsymbol{\alpha_{n-1}})\boldsymbol{b_n} \\ sin(\boldsymbol{\vartheta_n})sin(\boldsymbol{\alpha_{n-1}}) & cos(\boldsymbol{\vartheta_n})sin(\boldsymbol{\alpha_{n-1}}) & cos(\boldsymbol{\alpha_{n-1}}) & cos(\boldsymbol{\alpha_{n-1}})\boldsymbol{b_n} \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Rotation matrix $^{n-1}_{n}R$ Translation vector $^{n-1}_{n}t$

- The forward kinematics describe the transformation of the end-effector frame with respect to the base frame (i.e., frame 0) as a composition of D-H matrixes

$$_{e-e}^{0}T = {_1^0}T \dots {_{e-e}^{n-1}}T = \prod {_n^{n-1}}T = \begin{bmatrix} _{e-e}^{0}R & _{e-e}^{0}t \\ 0 \quad 0 \quad 0 & 1 \end{bmatrix}$$

- The position of the end-effector in the base frame (i.e., frame 0) ^{0}P is determined by the matrix-vector product of the composed D-H matrix with the position of the end-effector in the end-effector frame ^{e-e}P

    - The frame at the end-effector can be arbitrarily defined

$$^{0}P = {_{e-e}^{0}}T {^{e-e}}P$$

Descriptor of the forward kinematics

Four-joints and five links
planar robot

Link	b_n	ϑ_n	a_n	α_n
1	0	ϑ_1	a_1	0
2	0	ϑ_2	a_2	0
3	0	ϑ_3	a_3	0
4	0	ϑ_4	a_4	0

$$\,^0_4T = \,^0_1T \;^1_2T\,^2_3T \;^3_4T$$

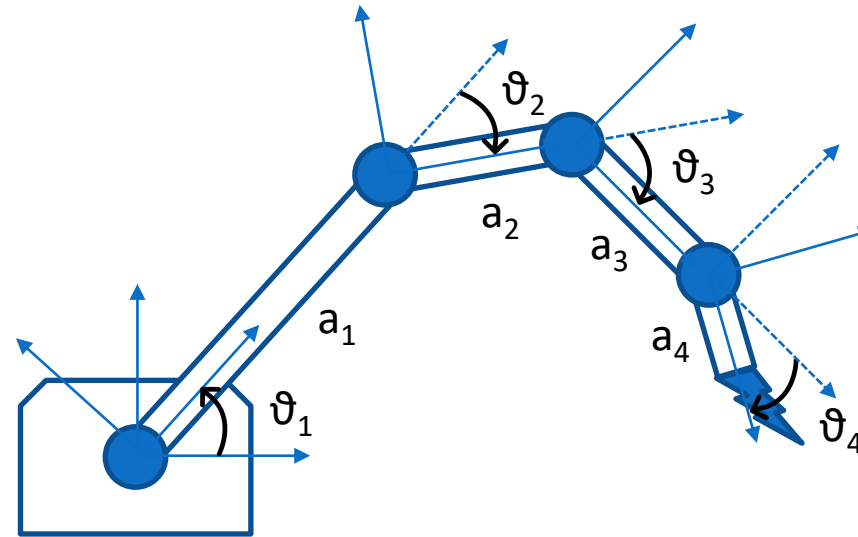$$\,^0_4T = \begin{bmatrix} cos(\vartheta_1) & -sin(\vartheta_1) & 0 & 0 \\ sin(\vartheta_1) & cos(\vartheta_1) & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} cos(\vartheta_2) & -sin(\vartheta_2) & 0 & a_1 \\ sin(\vartheta_2) & cos(\vartheta_2) & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} cos(\vartheta_3) & -sin(\vartheta_3) & 0 & a_2 \\ sin(\vartheta_3) & cos(\vartheta_3) & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} cos(\vartheta_4) & -sin(\vartheta_4) & 0 & a_3 \\ sin(\vartheta_4) & cos(\vartheta_4) & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

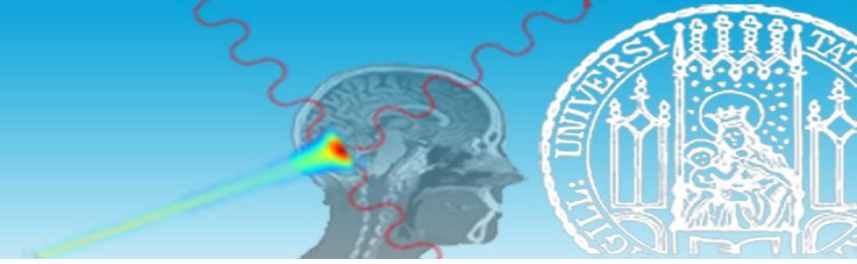- *Finally, we have to know where the robot goes…*

- The inverse kinematics problem is about the knowledge of the kinematic chain of the mechanical system, given the desired position of the end-effector (i.e., the task)

- The solution of the inverse kinematics problem is defined within the workspace of the mechanical system

  - If the task is outside the workspace, the solution does not exist

  - If the solution exists, this can be single or multiple (infinite) depending on the DoF of the mechanical system
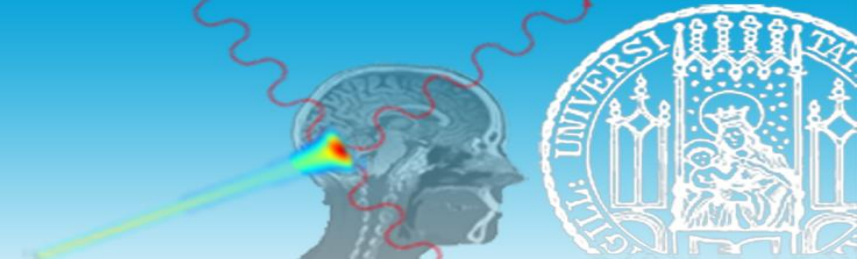
- The number of unknowns is defined by the DoF of the joints of the mechanical system

- The forward kinematics given by ${}_{e-e}^{0}T$ provide 16 equations but 4 of them are trivial. Among the remaining 12 equations, 3 equations are relevant to the position-vector ${}_{e-e}^{0}t$ and 9 equations are relevant the rotation-matrix ${}_{e-e}^{0}R$. In the rotation-matrix only 3 equations are independent. The number of equations is therefore 6.

- The kinematic equations are nonlinear and transcendental, their solution is not always easy (or even possible) in a closed-form

  - For a 6-DoF robot, there are 6 equations and 6 unknowns. In this case, the analytical solution of the inverse kinematic problem is feasible

- Numerical methods (i.e., iterative optimization algorithm) based on approximation and derivatives of the forward-kinematics function for finding the local minimum

- If n the number of joint variables, the forward-kinematics function maps a point in the joint space to an end-effector position in the workspace

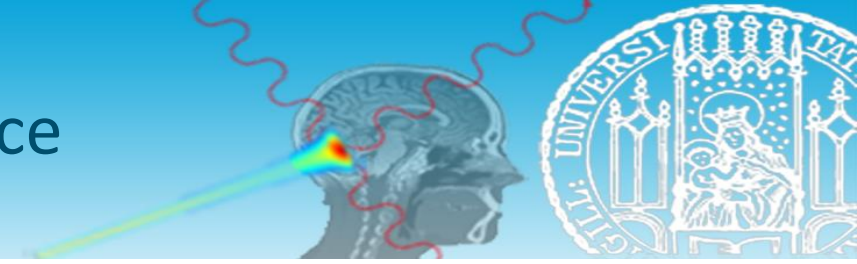$$p(x): \mathbb{R}^n \rightarrow \mathbb{R}^3$$

- Given the initial position of the system $p_0 = p(x_0)$, the task is defined as $p_1 = p(x_0 + \Delta x)$

- Given the Jacobian of the forward-kinematics function $J_p(x_0)$, whose size is 6 x n, the Taylor series expansion of the forward-kinematics function, valid for small Δx, is calculated as:

$$p(x_1) \approx p(x_0) + J_p(x_0)\Delta x$$

- By calculating the (pseudo) inverse $J_p^{inv}(x_0)$, the updating step is defined as:

$$\Delta x \approx J_p^{inv}(x_0)\Delta p(x_0) \qquad \text{with} \qquad \Delta p = p(x_0 + \Delta x) - p(x_0), \text{ and thus} \qquad \Delta x_{k+1} \approx J_p^{inv}(x_k)\Delta p_k$$
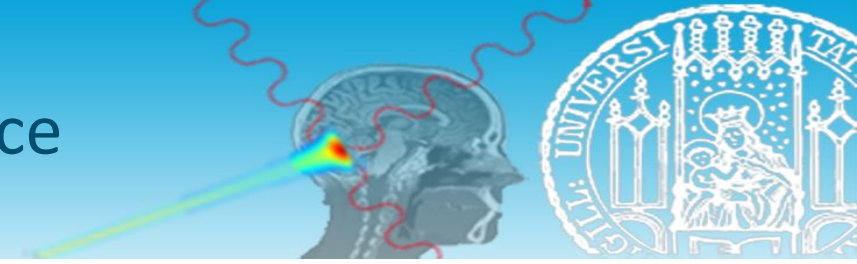
- The human body is a mechanical system made of joints and links that can implement a task

- The human senses define the control system that can provide information about the task

- The human brain is the intelligence system that can decide the task based on the sensor information

➡ artificial intelligence-driven robots
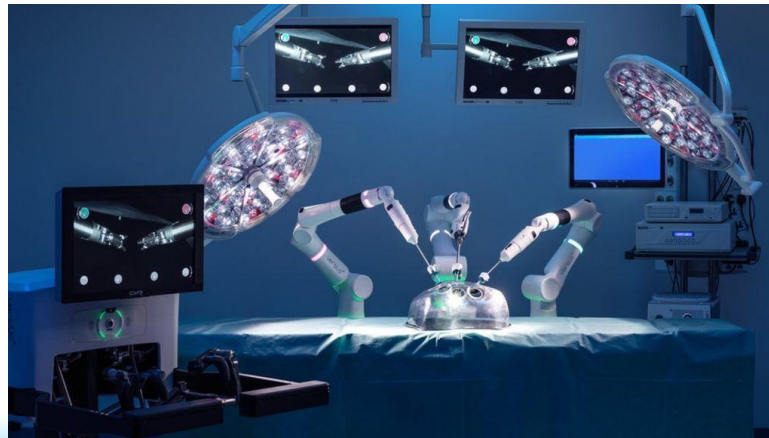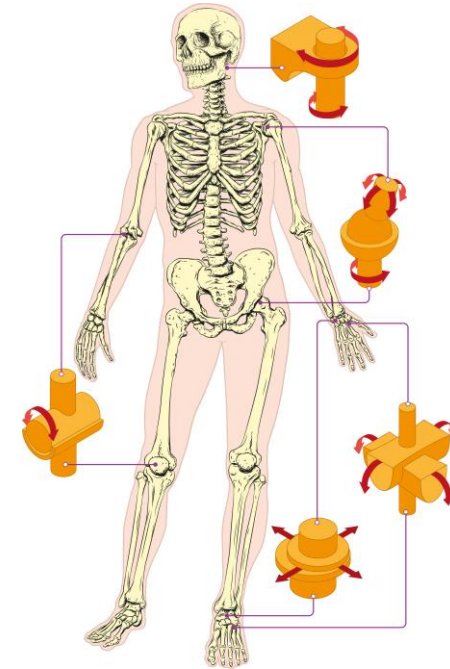
Robotic surgery

- In radiation oncology, the task is executed based on the patient model in the treatment planning scenario

- The task is adapted based on imaging and sensor systems for monitoring the treatment delivery scenario, thus adapting the *real* patient to the patient model (i.e., patient positioning) or vice versa, to adapt the patient model to the *real* patient (i.e., treatment adaptation and tumor tracking)

  - Correction models are defined (i.e., anatomical correction models, external-internal correlation models)
  - Model-free adaptive tasks based on AI