# Create Poly Correction Tables

#### Research Work Notes

## Back to single point – convergence is not consistent – 15/12/24

With LR at 0.1, sometimes it converges very well,

BUT:

1. Sometimes it reaches asymptotic convergence to high loss level
2. When gradient is negative, it still “correct” down and away from the target

#### Try another optimizer

I was using Adam.

Try single value input.

Try SGD

#### Try new approach – manual point-by-point convergence

I have all the information, at least for the “linear” case with a single volume.

## Single image train – 15/12/24

Use all radiuses for a single image.

What are their sources in the tables?

Start with a single table – than try 2 tables together.

## Single point train – continued – 15/12/24

1. Loss should return single value for single point
2. Gradient for a single point
3. Change only single point in table

Loss values are completely wrong. Check – through dump:

1. Tables
2. Images’ Volumes
3. Dev Maps
4. Loss

## Single point train by class CPolyDLTrainer0 – 10/12/24

1. First run on flat table –
   1. Save initial deviation map
   2. Identify target (for flatness)
2. **Second, try to change only one point**
3. Check difference
4. Identify hot point in dev diff
5. Save new dev map

Hottest point on diff is:

<data\_x> 30.106918 </data\_x>

<data\_y> 163.031235 </data\_y>

Fully consistent with computation

3) Define loss for a single point

## Make the training faster – 9/12/24

Do not need to repeat first and second recon each time…

May load ready target

#### Single point mode –

To make things simple – start with “impulse response” to some point…

Find the relevant point in the dev map

Give loss function only for this point – and optimize it!

#### Tube 0

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| row | det | max | im | rad |
| 70 | 300 | 2159.782 | 163 | 30 |

#### Tube 1

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| row | det | max | im | rad |
| 70 | 300 | 3805.391 | 67 | 30.218 |

## Working with Recon as external Function and Back Propagation – 9/12/24

C Ex Recon is working within training –

#### How to create meaningful gradients?

Start with a single point in the tables – and the corresponding single point in the Dev Map.

## Problems in integrating Recon as external function – 2/12/24

Work with C Ex Recon

It includes “forward” and “backward”

BUT – the backward format is not accepted!

## Try small input – 1/12/24

Try to use a small vector of ones as input!

## Start training on small matrices – 27/11/24

Questions:

1. How to select a small region where the dev map and poly table are both relevant?
2. What is the preferred artificial derivation for recon?

Thinking:

Start with central area:

1. Limited number of detectors
2. Limited number of rows
3. Limited number of images
4. Only small radiuses

In the central area I can easily use “Linear” with full connectivity…

Target is flat deviation map – flat value is taken from empty map

#### Data dimensions

Dev Map is 280 images \* 128 radiuses 🡺

## Now I know how to integrate external function in loss function – 27/11/24

Example is in “D:\SW\TrainDL - ExFunc example”

## Ideas for using DL to create poly tables – 26/11/24

Input can be one or several Deviation Maps.

The connections can be spatially oriented – for each location use only relevant input space.

#### Gradual approach

1. Do some training for fully connected
2. Use central area of a few images for small input and output matrices
3. Use BP results for loss function
4. …

## Create real DL prototype – 25/11/24

New Spyder project at “D:\SW\PolyDL”

INPUT for DL:

The Dev Map – 280\*260

NN:

All 2 All, few layers

Output – the fraction part of the 1st coefficient – valued between -0.01 and +0.01

Output size is 192 \* 668

Try training initially for flat table!

## After discussion – 22/11/24

1. Where are the edges of the water phantom container?
   1. They are well seen in FOV 450
2. Galit suggest to separate data by FOV – set new sets of data
   1. New data from Galit is in “h:\Poly Calibration by AI\From Galit 2”
3. I promise to try to create a prototype with real DL where recon is used only as LOSS

## Prepared presentation for Physics team – 21/11/24

Presentation is under GIT in:

D:\SW\PyIP\Docs

Result Driven Preparation of Poly Correction Tables - Initial Research Report.pptx

## Use IIR to correct poly tables – 16/11/24

Optimizing to target is working – but poorly!

1. The target itself is usually not improving - First check why?
2. Make more bold steps

#### Check how the target is missed…

The correction is not at the exact position to improve the target!

First make the errors apparent – check their direction!

Find location and direction of most change in the new [image, radius] raster

#### New flow: Several steps per target

First select a target to correct

Then take several steps until it is significantly improved (at least 40%)

For each target there are 4 spatial options: Each of the 2 tubes, Left & Right

One of the tubes may not be effective.

## Use IIR to correct poly tables – 2/11/24

Some ideas:

1. Separate the “abs diff from target” score from all other scores
   1. Try accepting steps only by “average abs diff”
   2. Make sure that the max point that was targeted really improved
2. Maybe try correcting both tubes – and see which one is better?
3. Select patches of different radius for deviations of different size
   1. Prepare several initial patches
4. Avoid traps of repeatedly trying to correct failed corrections

## Use IIR to correct poly tables – 2/11/24

Add global log to help understand how steps are selected and what is the result

## Use IIR to correct poly tables – 30/10/24

Set a single target-level and strive to bring all rings to this level.

Find point with biggest deviation from target – and select relevant correction.

Direction of correction (up or down) is evident from the selected deviation.

After correction & recon, consider both local and global deviation score.

Later this method will also help to decide width and amplitude of correction.

Avoid marginal spaces – at least initially.

#### Create new “score” – distance from flat target at ring

Dump Deviation [Image, Radius] as displayable matrix

Apparently, there are very strong deviations on the margins –

Try to cut out the margins! Peel function seems to work OK.

#### First verify that problems are correctly identified

Even after peel – result seems to be wrong!

self.avgDev=-1.0128281116485596, iImage=92, iRad=0, maxDev=tensor(-458.4808)

Second run even worse:

self.avgDev=-0.9682614803314209, iImage=92, iRad=0, maxDev=tensor(-999.0014)

The inner rings should be deterministic – as there are only 4 pixels!

Something is basically wrong with the average per radius computations!

## Check IR and IIR in a single automatic loop – 29/10/24

In Identify Ring Source.py

First activate new recon option:

Set config file “d:\Config\Poly\Impulse.txt”: Tube, row, detector

Set BP dump name at: “d:\Config\Poly\BPDumpFileName.txt”

To something like: “d:/PolyCalib/Impulse\Poli\_AI\_t1\_r70\_d300\_width256\_height256\_zoom2.float.rvol”

## Correcting table by Reverse-IR function – 23-27/10/24

Work with new “impulse response values” to check full loop of IIR

D:\PolyCalib\Impulse

Poli\_AI\_t1\_r70\_d300\_width256\_height256\_zoom2.float.rvol

Load it and analyze it – to find source of ring!