Single Shell Free Water Elimination Model Implementation Notes

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1 Introduction

This document details out an implementation of a Free Water Elimination model for Diffusion Tensor MRI. We are mainly following the implementation in [Pasternak2009] with a few simplifications suggested in [Pasternak2014].

2 Bi-tensor Model

In this section we summarize the **Theory** section in [Pasternak2009].

For each voxel we have several readings. $\mathbf{S}_0$ is the signal acquired for the zero diffusion weighting from the **b0** image. $\mathbf{S}_k$ is the signal from the diffusion weighted image (DWI) when the gradient orientation $\mathbf{q}_k$ is applied. We calculate the attenuation $[\hat{\mathbf{A}}]_k = \mathbf{S}_k/\mathbf{S}_0$. The attenuation values are between 0 and 1.

For the **single compartment model** we assume that the attenuation $[\hat{\mathbf{A}}]_k$ all comes from tissue $[\mathbf{A}_{\text{tissue}}]_k$. For a Diffusion Tensor $\mathbf{D}$ this gives us

$$[\mathbf{A}_{\text{tissue}}(\mathbf{D})]_k = \exp(-b\mathbf{q}_k^T\mathbf{D}\mathbf{q}_k).$$

The b value in the equation is above is the b-value of our single shell. The gradient $\mathbf{q}_k$ is a vector of length 3 and $\mathbf{D}$ is a 3x3 symmetric matrix at each voxel. Let's denote by n the number of applied gradients. The minimum n required is 6 as $\mathbf{D}$ has 6 parameters that need to be estimated at each voxel. Usually we have a large number (somewhere between 30 and 60)

If we had water instead of tissue at the voxels then the DTI model (above) simplifies and we get the same result in all directions. The matrix $\mathbf{D}$ becomes a scalar d and we get the same value of attenuation at every voxel.

$$[\mathbf{A}_{\text{water}}]_k = \exp(-bd),$$

where $d = 3 \cdot 10^{-3}$ mm^2/s for water at 37°C.

For the **bi-tensor model** we assume that each voxel has a two compartments. One compartment contains tissue and one contains free water. Let f be the fraction of the volume that is free water. Then we have

$$[\mathbf{A}_{\text{bi-tensor}}(\mathbf{D}, f)]_k = (1-f)[\mathbf{A}_{\text{tissue}}(\mathbf{D})]_k + f[\mathbf{A}_{\text{water}}]_k$$

f is a scalar that needs to be estimated for each voxel. $(0 \leq f < 1)$

Note: This is a departure from the notation in [Pasternak2009] which interchanges the values of f and $1-f$. This is done so that we maintain compatibility with the multi-shell free water elimination implementation in DIPY.

To fit the bi-tensor model we would like to estimate the best values of $\mathbf{D}$ and f that fit

$$[\hat{\mathbf{A}}]_k = [\mathbf{A}_{\text{bi-tensor}}(\mathbf{D}), f)]_k$$

We need to estimate a scalar f and a real symmetric matrix $\mathbf{D}$ at each voxel. This is solvable if $f = 0$ everywhere and we are looking at a single compartment model. However, if f is a parameter to be estimated at each voxel then there are infinitely many viable solutions. Choosing amongst them requires additional constraints.

3 Variational Framework

$$L(\mathbf{D}, f) = \int_\Omega \left(||\mathbf{A}_{\text{bi-tensor}}(\mathbf{D}, f) - \hat{\mathbf{A}}|| + \alpha\sqrt{|\gamma(\mathbf{D})|} \right) d\Omega$$

Here α is a parameter to control the regularization

4 Induced Metric

Instead of using the natural Riemannian metric on the spatial-feature space as given in [Pasternak2009], we use the Euclidean metric given in [Pasternak2014]

$$h = \begin{pmatrix} 1 &&&&&&&& \\ & 1 &&&&&&& \\ && 1 &&&&&& \\ &&& \beta &&&&& \\ &&&& \beta &&&& \\ &&&&& \beta &&& \\ &&&&&& \beta && \\ &&&&&&& \beta & \\ &&&&&&&& \beta \end{pmatrix}$$

for some $\beta > 0$. Also the embedding is given by

$$\mathbf{x} = [x, y, z, D^{11}, D^{22}, D^{33}, \sqrt{2}D^{12}, \sqrt{2}D^{23}, \sqrt{2}D^{13}].$$

We can pull this metric back to get the induced metric. The components of the induced metric are given in Einstein's summation notation by

$$\gamma_{\mu\nu} = \partial_\mu \mathbf{x}^i \partial_\nu \mathbf{x}^j h_{ij}(\mathbf{x}).$$

The indices μ and ν take values 1, 2 or 3 which correspond to the x, y, and z directions. The co-ordinates of the spatial-feature space are denoted by $\mathbf{x}^i$ and the indices i and j take values 1 to 9. Since h is diagonal h_{ij} is only non-zero when $i = j$. So the double sum over i and j become a single sum over either one of the indices. Expanding this out we get

$$\gamma_{\mu\nu} = \sum_{i=1}^{3} \partial_\mu \mathbf{x}^i \partial_\nu \mathbf{x}^i + \beta \sum_{i=4}^{9} \partial_\mu \mathbf{x}^i \partial_\nu \mathbf{x}^i$$

The γ matrix is symmetric so we only need to write out 6 equations.

$$
\begin{aligned}
\gamma_{11} &= 1+\beta\sum_{i=4}^{9}\left(\mathbf{x}_x^i\right)^2 \\
\gamma_{22} &= 1+\beta\sum_{i=4}^{9}\left(\mathbf{x}_y^i\right)^2 \\
\gamma_{33} &= 1+\beta\sum_{i=4}^{9}\left(\mathbf{x}_z^i\right)^2 \\
\gamma_{12} &= \beta\sum_{i=4}^{9}\mathbf{x}_x^i\mathbf{x}_y^i \\
\gamma_{23} &= \beta\sum_{i=4}^{9}\mathbf{x}_y^i\mathbf{x}_z^i \\
\gamma_{13} &= \beta\sum_{i=4}^{9}\mathbf{x}_x^i\mathbf{x}_z^i
\end{aligned}
$$

The subscripts x, y, z denote partial derivatives w.r.t those co-ordinates. We denote the determinant of the matrix $\gamma_{\mu\nu}$ by $|\gamma|$. We also denote the inverse of the $\gamma_{\mu\nu}$ matrix by $\gamma^{\mu\nu}$. Since the inverse of an invertible matrix is the transpose of the co-factor matrix divided by the determinant, these two quantities are related by

$$\gamma^{\mu\nu} = \frac{C_{\nu\mu}}{|\gamma|}$$

The cofactor $C_{\nu\mu}$ is computed by $C_{\nu\mu} = (-1)^{\nu+\mu}M_{\nu\mu}$ where $M_{\nu\mu}$, a minor, is the determinant of the sub-matrix of γ with the ν-th row and μ-th column removed. Since γ is symmetric, its inverse matrix is also symmetric. This means that we do not need to take the transpose of the co-factor matrix and can also use the identity

$$\gamma^{\mu\nu} = \frac{C_{\mu\nu}}{|\gamma|}.$$

$$
\begin{aligned}
C_{11} &= (\gamma_{22}\gamma_{33} - \gamma_{23}^2) \\
C_{22} &= (\gamma_{11}\gamma_{33} - \gamma_{13}^2) \\
C_{33} &= (\gamma_{11}\gamma_{22} - \gamma_{12}^2) \\
C_{12} &= (-\gamma_{12}\gamma_{33} + \gamma_{13}\gamma_{23}) \\
C_{23} &= (-\gamma_{11}\gamma_{23} + \gamma_{13}\gamma_{12}) \\
C_{13} &= (\gamma_{12}\gamma_{23} - \gamma_{13}\gamma_{22})
\end{aligned}
$$

We also calculate the determinant as the expansion of the co-factors along the first row.

$$
|\gamma| = \gamma_{11}C_{11} + \gamma_{12}C_{12} + \gamma_{13}C_{13}
$$

5 Gradient Descent

The equations of motion in [Pasternak2009][A8] simplify with this new choice of metric h as the Christoffel numbers are zero. For the 6 tensor elements $j \in 4, 5, \ldots, 9$,

$$
\Delta \mathbf{x}^j = b \sum_{k=1}^{n} (\hat{\mathbf{A}} - \mathbf{A}_{\text{bi-tensor}}) \mathbf{A}_{\text{tissue}} \left(\mathbf{q}_k^T \frac{\partial \mathbf{D}}{\partial \mathbf{x}^j} \mathbf{q}_k \right) + \frac{\alpha}{\sqrt{|\gamma|}} \partial_\mu (\sqrt{|\gamma|} \gamma^{\mu\nu} \partial_\nu \mathbf{x}^j)
$$

where Einstein's summation notation is used in the second term on the right hand side. For the fractional volume parameter we have

$$
\Delta f = -b \sum_{k=1}^{n} (\hat{\mathbf{A}} - \mathbf{A}_{\text{bi-tensor}})(\mathbf{A}_{\text{tissue}} - \mathbf{A}_{\text{water}})
$$

5.1 Beltrami Operator

Here we write out the expression for the Beltrami operator Δ_γ

$$
\Delta_\gamma \mathbf{x}^j = \frac{1}{\sqrt{|\gamma|}} \partial_\mu (\sqrt{|\gamma|} \gamma^{\mu\nu} \partial_\nu \mathbf{x}^j)
$$

This expression is in Einstein Summation notation and μ and ν go from 1 to 3. So we have 9 expressions that we consider 3 at a time.

Setting $\mu = 1$ we get three terms by letting ν go from 1 to 3.

$$\begin{aligned}
& \frac{1}{\sqrt{|\gamma|}}\frac{\partial}{\partial x}(\sqrt{|\gamma|}\gamma^{11}\mathbf{x}_x^j + \sqrt{|\gamma|}\gamma^{12}\mathbf{x}_y^j + \sqrt{|\gamma|}\gamma^{13}\mathbf{x}_z^j) \\
= \;& \frac{1}{\sqrt{|\gamma|}}\frac{\partial}{\partial x}\left(\frac{C_{11}}{\sqrt{|\gamma|}}\mathbf{x}_x^j + \frac{C_{12}}{\sqrt{|\gamma|}}\mathbf{x}_y^j + \frac{C_{13}}{\sqrt{|\gamma|}}\mathbf{x}_z^j\right) \\
= \;& \frac{1}{\sqrt{|\gamma|}}\frac{\partial}{\partial x}\left(\frac{p^j}{\sqrt{|\gamma|}}\right), \quad \text{Setting} \quad p^j = C_{11}\mathbf{x}_x^j + C_{12}\mathbf{x}_y^j + C_{13}\mathbf{x}_z^j \\
= \;& \frac{p_x^j}{|\gamma|} - \frac{p^j\gamma_x}{2|\gamma|^2}, \quad \text{Using the quotient rule.}
\end{aligned}$$

Setting $\mu = 2$ and $q^j = C_{12}\mathbf{x}_x^j + C_{22}\mathbf{x}_y^j + C_{23}\mathbf{x}_z^j$, we get the next three terms as

$$\frac{q_x^j}{|\gamma|} - \frac{q^j\gamma_x}{2|\gamma|^2}$$

Similarly, setting $\mu = 3$ and $r^j = C_{13}\mathbf{x}_x^j + C_{23}\mathbf{x}_y^j + C_{33}\mathbf{x}_z^j$, we get the next three terms as

$$\frac{r_x^j}{|\gamma|} - \frac{r^j\gamma_x}{2|\gamma|^2}$$

Note: The definition of p^j and q^j is a generalization of the ones given in the discretization of the Beltrami flow given in [Kimmel] (Equations 10.4 and 10.5).

Putting it all together

$$\Delta_\gamma \mathbf{x}^j = \frac{1}{|\gamma|}(p_x^j + q_y^j + r_z^j) - \frac{1}{2|\gamma|^2}(p^j\gamma_x + q^j\gamma_y + r^j\gamma_z).$$

References

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