

# SPATIALLY VARIABLE DECONVOLUTION FOR LIGHTSHEET MICROSCOPY

Bogdan Toader<sup>1</sup>, Stéphane Chrétien<sup>2</sup>, Andrew Thompson<sup>3</sup>

<sup>1</sup>University of Cambridge, <sup>2</sup>University of Lyon 2, <sup>3</sup>National Physical Laboratory



UNIVERSITY OF  
CAMBRIDGE

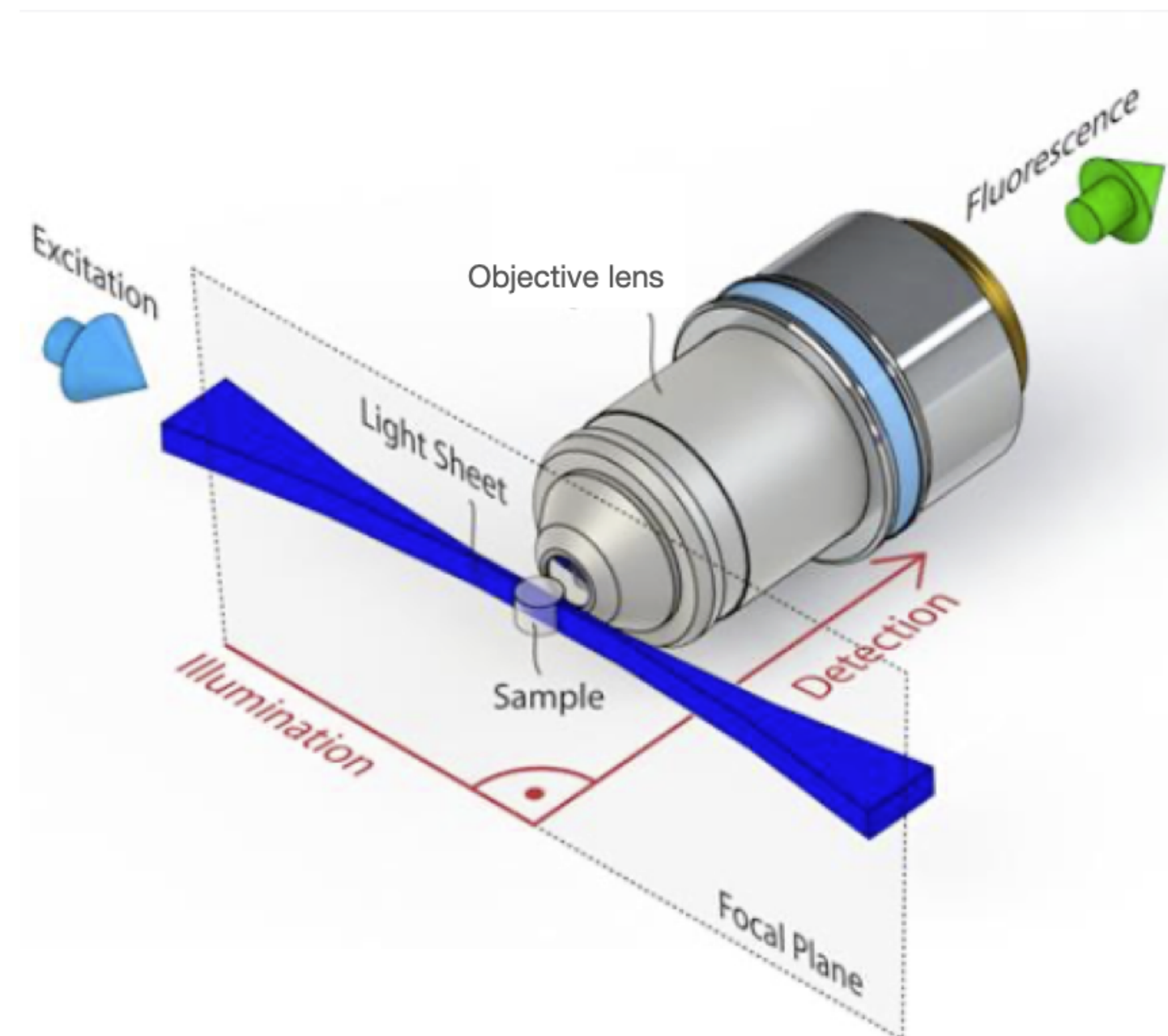
## LIGHTSHEET MICROSCOPY

TODO: a few words about why lightsheet is good

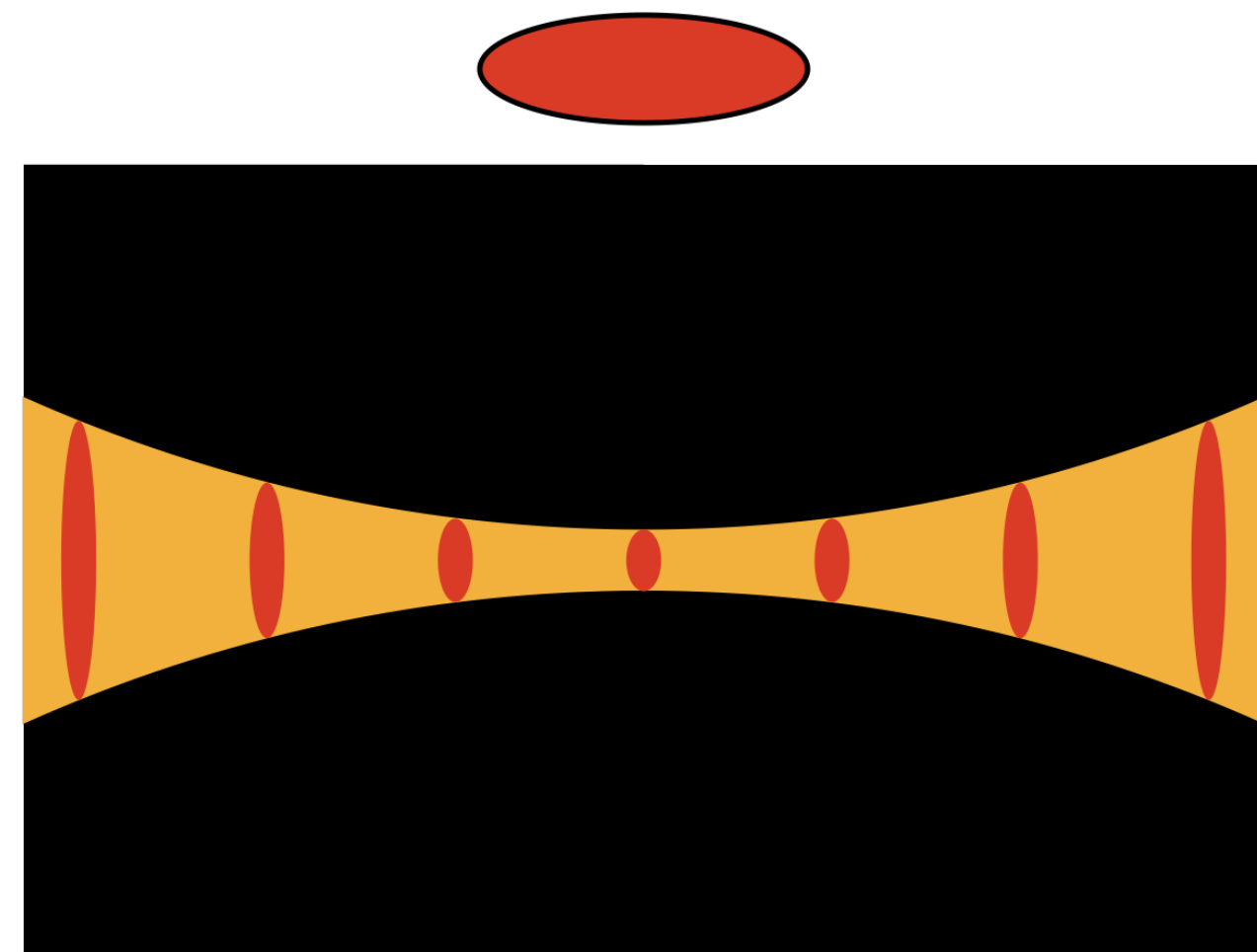
Light sheet microscopy is a type of fluorescence microscopy used in cell biology due to its fast acquisition times and low photo-damage to the sample. This is achieved by selectively illuminating a slice of the sample using a sheet of light and detecting the emitted fluorescence signal using a dedicated objective orthogonal to the plane of the sheet.

- Project aim: computationally improve the quality of light sheet microscopy images.

### LIGHT-SHEET MICROSCOPE



### SPATIALLY VARYING PSF



### PROBLEM

Due to the combination of light-sheet and the objective PSF, the effective PSF of the system is spatially varying, and therefore standard deconvolution approaches are not applicable.

Figure credit: Jörg Ritter, PhD thesis (2011)

A light-sheet microscope consists of two objectives: TODO etc

## MODEL

The measure  $x$  can be recovered exactly by solving the TV norm minimisation problem over non-negative measures  $z$  on  $[0, 1]$ :

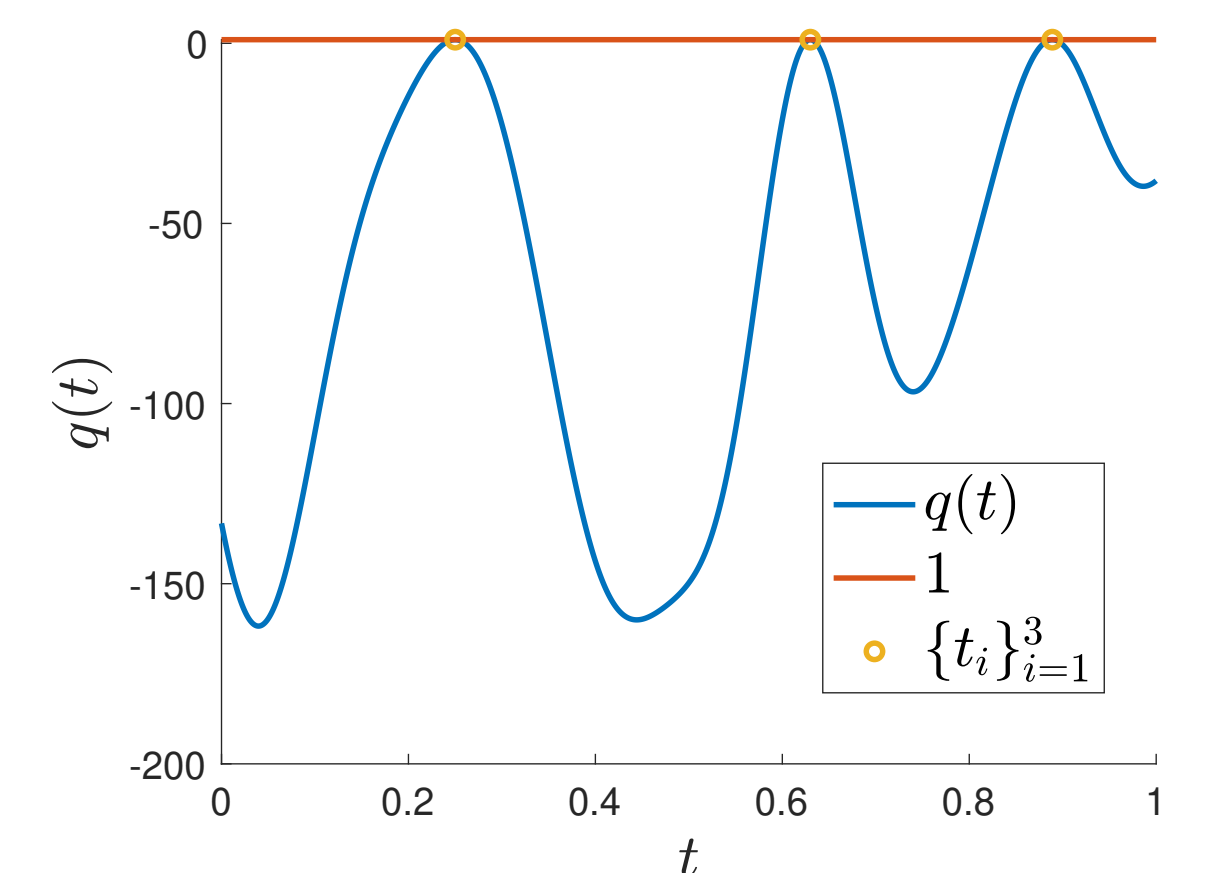
$$\min_{z \geq 0} \|z\|_{TV} \quad \text{subject to} \quad y_j = \int_{[0,1]} \phi(t - s_j) x(dt), \quad \forall j = 1, \dots, m, \quad (1)$$

or its dual:

$$\max_{\lambda \in \mathbb{R}^m} y^T \lambda \quad \text{subject to} \quad \sum_{j=1}^m \lambda_j \phi(t - s_j) \leq 1, \quad \forall t \in [0, 1]. \quad (2)$$

Having the solution  $\lambda$  to the dual problem (2), the locations  $\{t_i\}_{i=1}^k$  in the input signal are given by the global maximisers of the dual certificate:

$$q(t) = \sum_{j=1}^m \lambda_j \phi(t - s_j).$$



## RESULTS – SIMULATED DATA

## FITTING THE PSF

### ALGORITHM

We solve  $\min_{\lambda \in \mathbb{R}^m} f(\lambda)$  for the exact penalty  $f$ :

$$f(\lambda) = -y^T \lambda + \Pi \cdot \max\left\{\sup_s \sum_{j=1}^m \lambda_j \phi(s - s_j) - 1, 0\right\}$$

in the set  $Q = \{\lambda \in \mathbb{R}^m \mid \|\lambda\|_\infty \leq B\}$ . As described in [1], at every iteration  $p$ :

1. Compute the piece-wise linear model:

$$\hat{f}_p(\lambda) = \max_{0 \leq l \leq p} \left[ f(\lambda_l) + \langle g(\lambda_l), \lambda - \lambda_l \rangle \right],$$

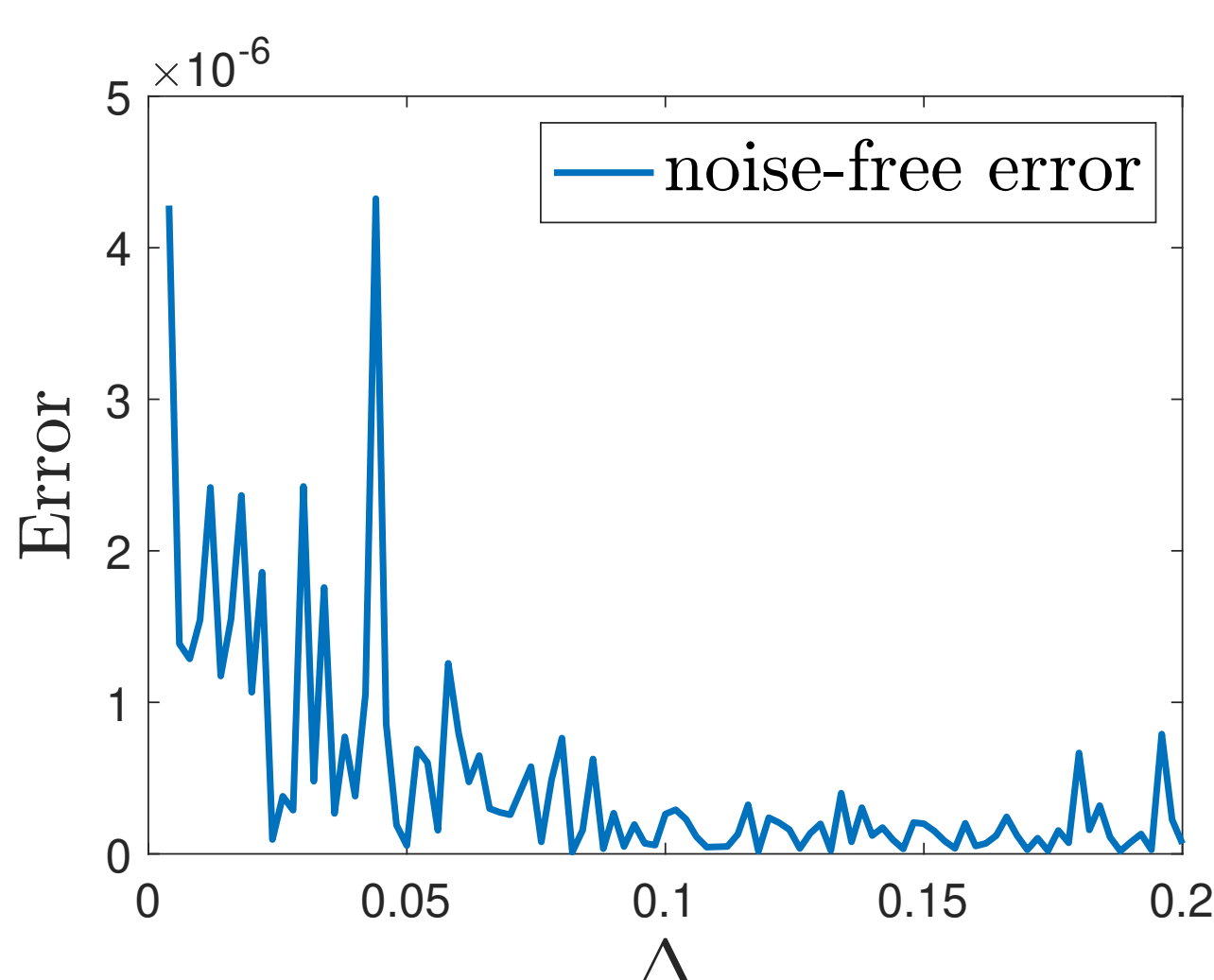
where  $g(\lambda_l)$  are some subgradients of  $f$  at  $\lambda_l$ .

2. Find the optimal value  $\hat{f}_p^*$  of the current model  $\hat{f}_p$  and the smallest value  $f_p^*$  of the objective  $f$  so far.
3. Calculate the next iterate  $\lambda_{p+1}$  as the projection of  $\lambda_p$  on the level set  $\mathcal{L}_p(\alpha) = \{\lambda \in Q \mid \hat{f}_p(\lambda) \leq \ell_p(\alpha)\}$  where  $\ell_p(\alpha) = (1 - \alpha)\hat{f}_p^* + \alpha f_p^*$  for some  $\alpha \in (0, 1)$ .

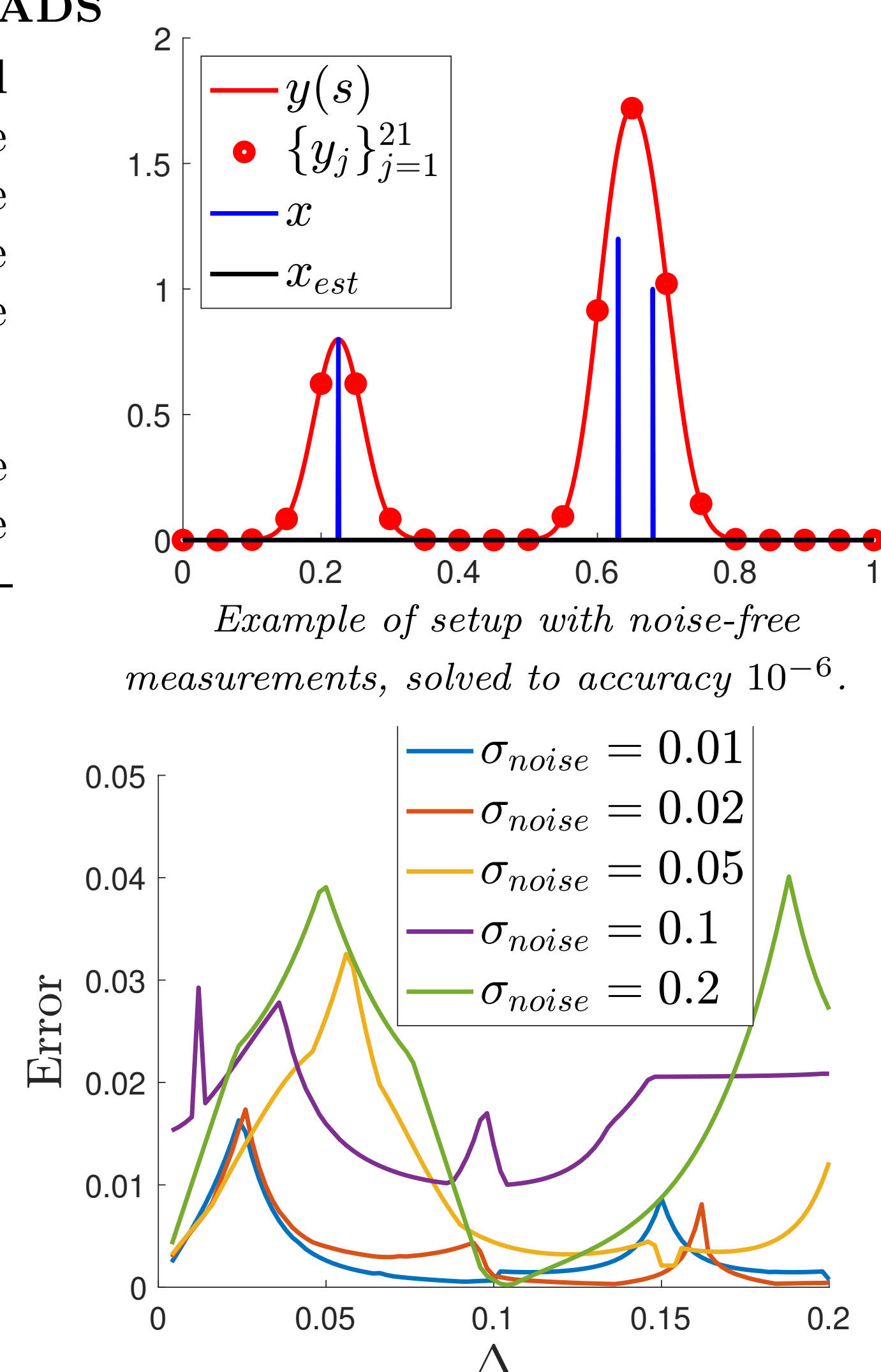
## RESULTS – REAL DATA

### BEADS

- **Exact measurements:** the level method finds the correct locations of the point sources with high accuracy – see the localisation error for two sources as the distance between them goes to zero in the bottom left figure.
- **Noisy measurements:** As the distance between two sources decreases, they are replaced with one source with higher intensity in the reconstructed signal.

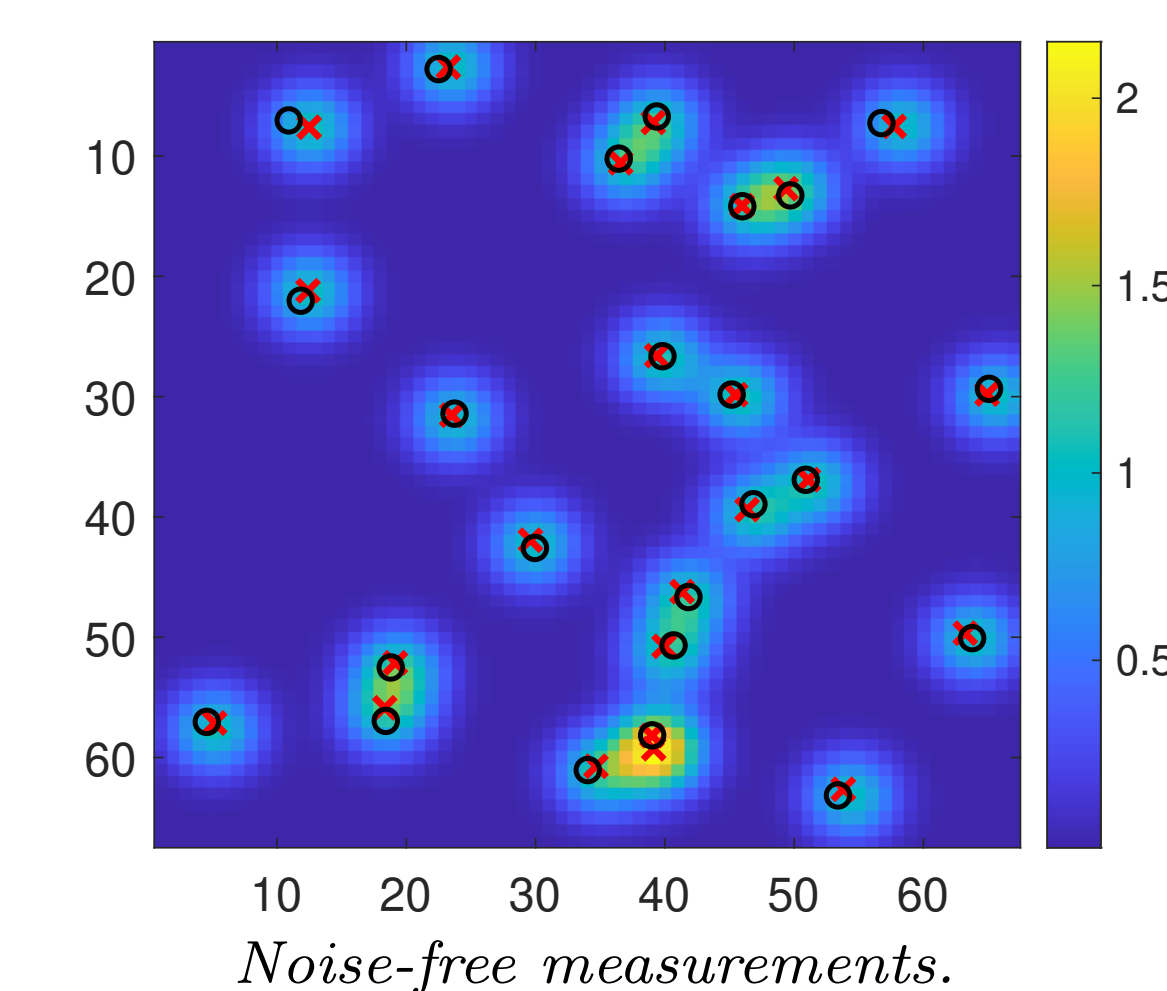


Localisation error for two point sources as the distance  $\Delta$  between them increases from 0.004 to 0.2 in the noise-free case (left) and noisy case for Gaussian noise with standard deviation 0.01, 0.02, 0.05, 0.1, 0.2 (right). The convolution kernel is Gaussian with  $\sigma = 0.05$ , intensities are 1 and  $m = 21$  equispaced samples.

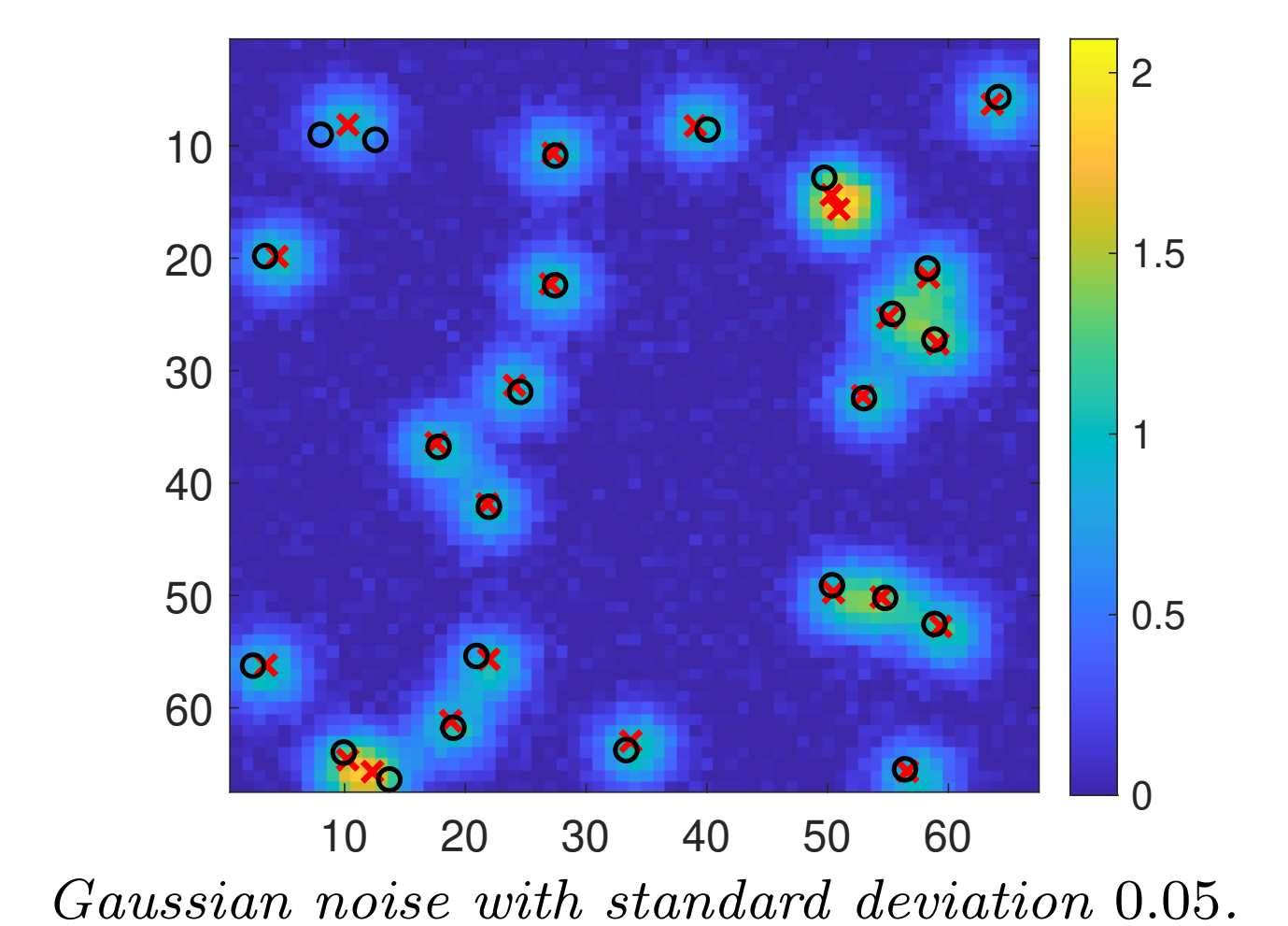


### MARCHANTIA

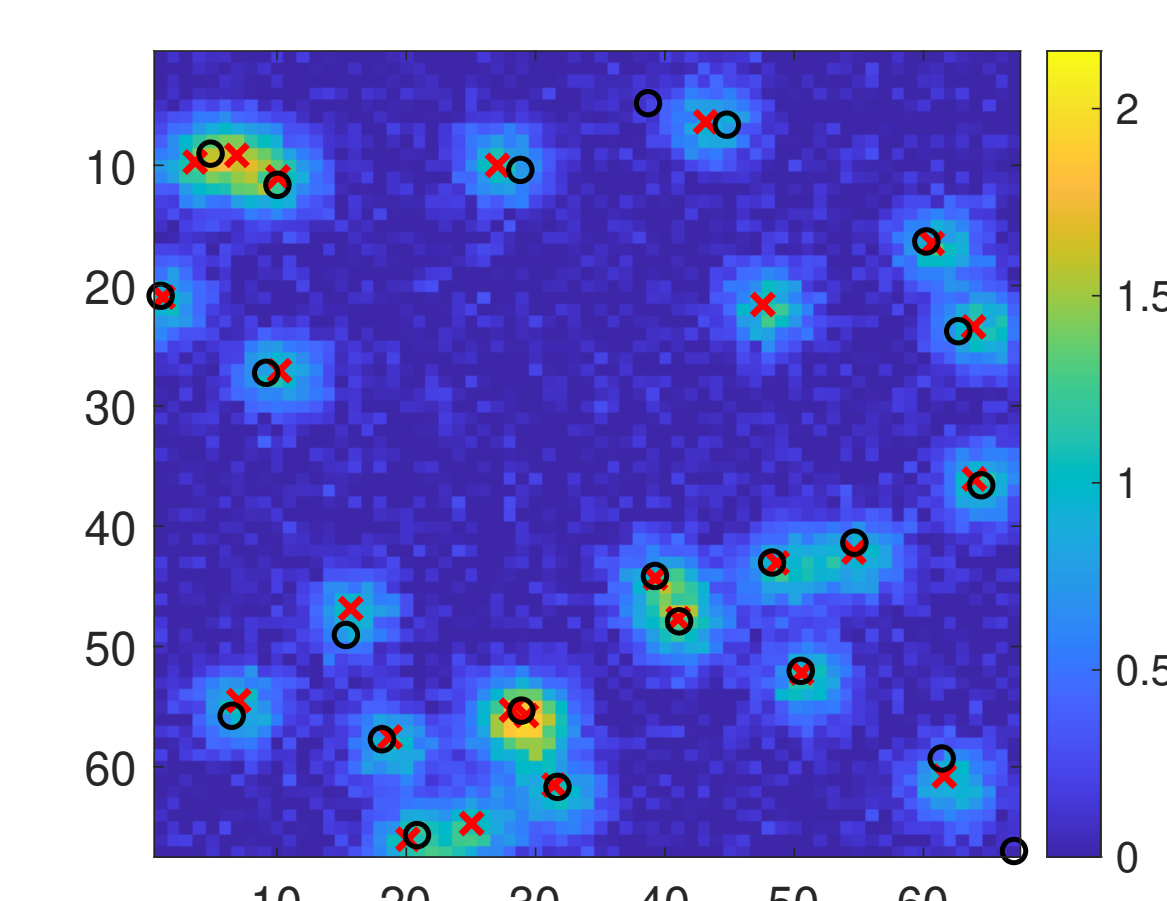
Examples of  $k = 25$  sources in an image with  $67 \times 67$  pixels (giving  $m = 4489$  measurements), Gaussian kernel with  $\sigma = 0.05$  and level method parameters  $\Pi = 100$  and  $B = 100$ . Red crosses  $\times$  are true sources and black circles  $\circ$  are estimated sources.



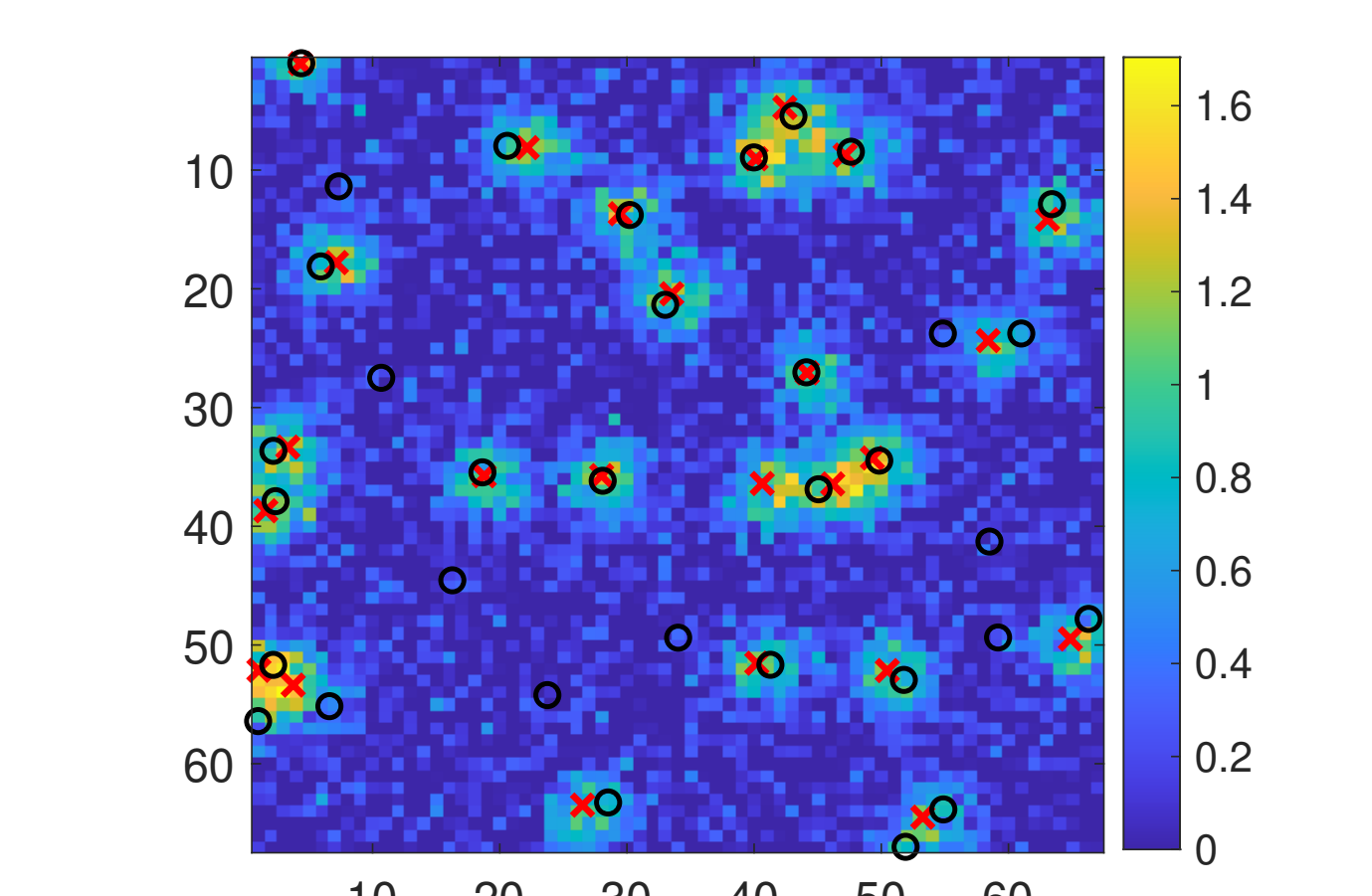
Noise-free measurements.



Gaussian noise with standard deviation 0.05.



Gaussian noise with standard deviation 0.1.



Gaussian noise with standard deviation 0.2.