



Uncertainty in multitask learning: joint representations for probabilistic MR-only radiotherapy treatment planning

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Sebastien Ourselin, Daniel C. Alexander, Jamie R. McClelland and M. Jorge Cardoso



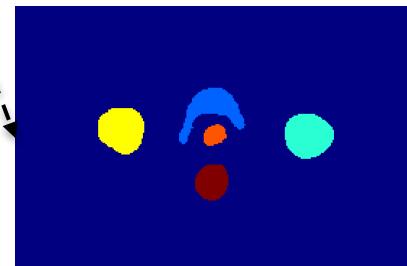
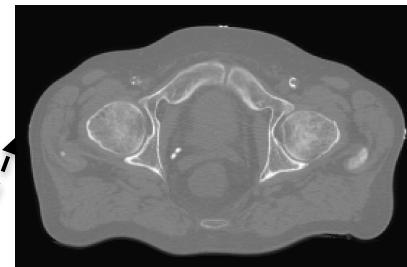
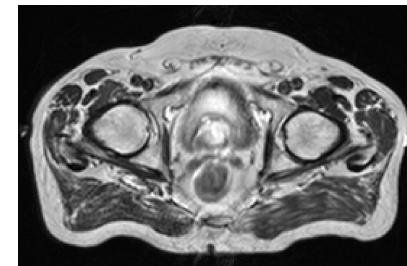
Poster M-101

21st International Conference on Medical Image Computing
& Computer Assisted Intervention (MICCAI 2018)
September 2018, Granada

MR-only radiotherapy treatment planning

- MR-only radiotherapy treatment planning requires the simultaneous
 - a) synthesis of a CT scan (synCT) from MRI
 - b) segmentation of organs at risk (OAR) from MRI
- Main goal
 - a) Multi-task learning for simultaneous regression and segmentation
 - b) Probabilistic deep learning to acquire uncertainties in the prediction of the network

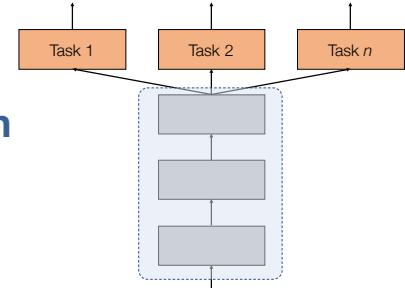
MRI



Organ
segmentation

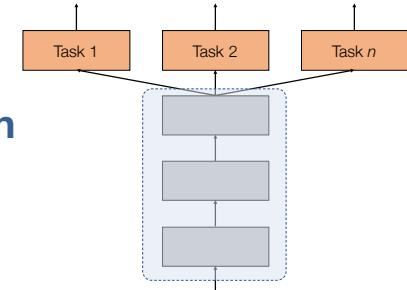
Multi-task feature learning

- Medical image analysis aims to learn a **common anatomical representation**
- Learn a non-linear mapping from this feature space to minimise a loss
- *How to minimise this loss in a multi-task setting?*



Multi-task feature learning

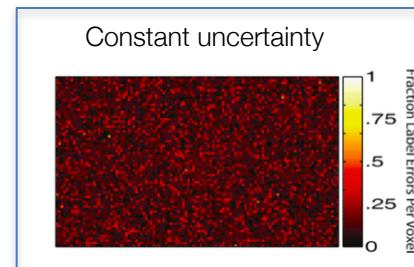
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- Learn a non-linear mapping from this feature space to minimise a loss
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- Most methods do not consider that uncertainty in the task varies depending on the spatial location



Ground truth labels



Constant uncertainty



Observed uncertainty

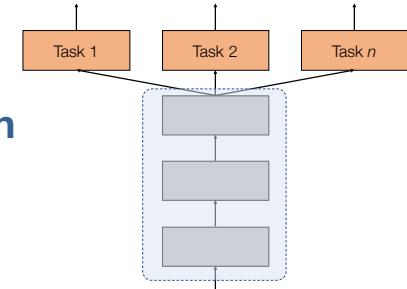


Figure adapted
from Asman et. al.,
IEEE TMI 2011

- Allows us to exploit this property (heteroscedasticity) for a natural mechanism for weighting task losses

Multi-task feature learning

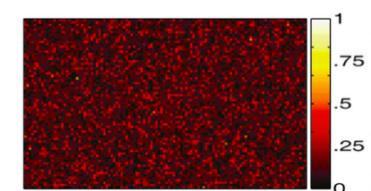
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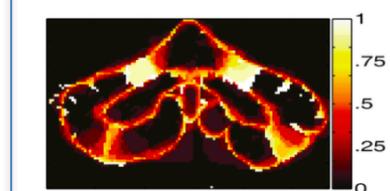
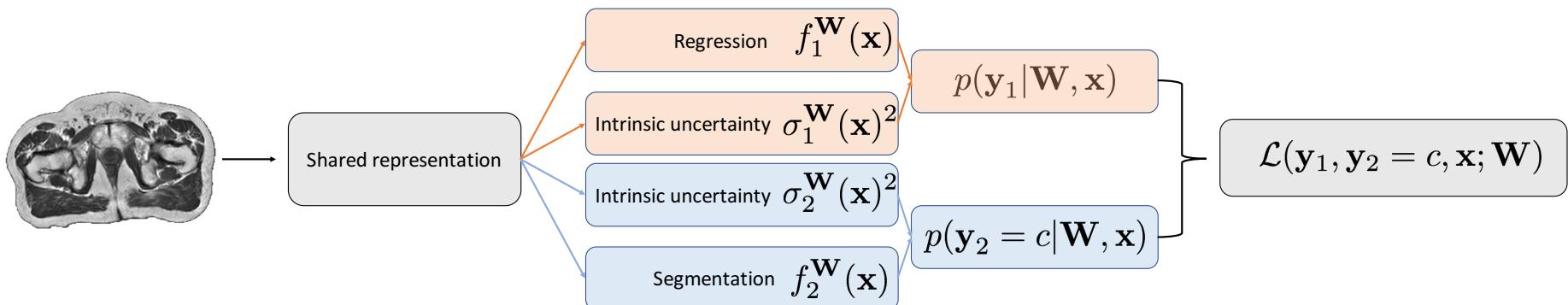


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- Allows us to exploit this property (heteroscedasticity) for a natural mechanism for weighting task losses

Our contribution

- Probabilistic dual-task network with hard-parameter sharing
 - Shared representation network + **regression** and **segmentation** specific branches
- Predict task-specific heteroscedastic uncertainty for spatially adaptive task loss weighting
- Approximate Bayesian inference to also capture uncertainty in the model weights

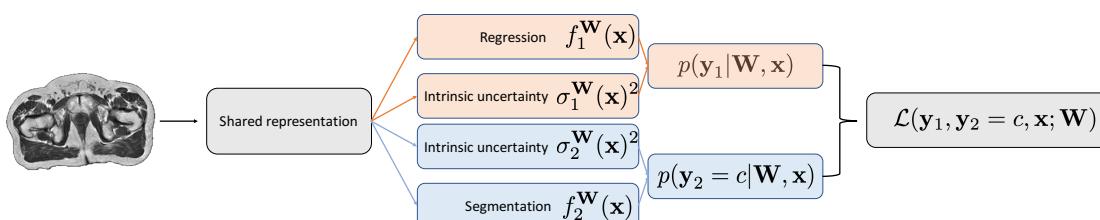


Our contribution

- Multi-task likelihood:

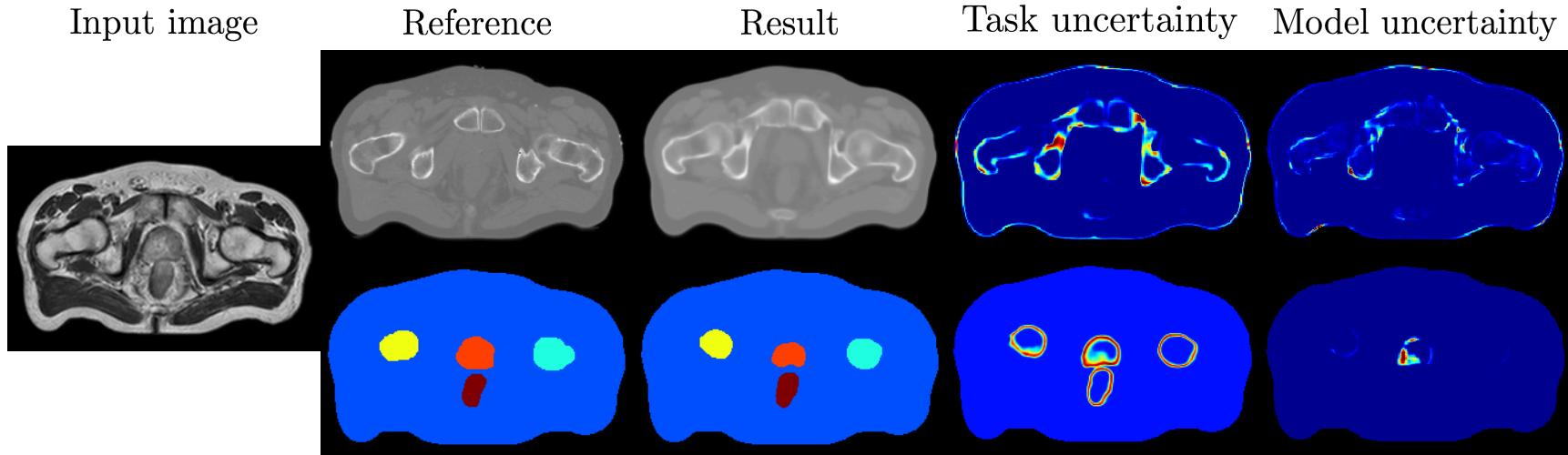
$$\mathcal{L}(\mathbf{y}_1, \mathbf{y}_2 = c, \mathbf{x}; \mathbf{W}) = \frac{\|\mathbf{y}_1 - f_1^{\mathbf{W}}(\mathbf{x})\|^2}{2\sigma_1^{\mathbf{W}}(\mathbf{x})^2} + \frac{\text{CE}(f_2^{\mathbf{W}}(\mathbf{x}), \mathbf{y}_2 = c)}{2\sigma_2^{\mathbf{W}}(\mathbf{x})^2} + \log\left(\sigma_1^{\mathbf{W}}(\mathbf{x})^2 \sigma_2^{\mathbf{W}}(\mathbf{x})^2\right)$$

- Separate networks to predict:
 - Regression and segmentation per voxel: $f_1^{\mathbf{W}}(\mathbf{x})$, $f_2^{\mathbf{W}}(\mathbf{x})$
 - Spatially adaptive weighting using heteroscedastic uncertainty: $\sigma_1^{\mathbf{W}}(\mathbf{x})^2$, $\sigma_2^{\mathbf{W}}(\mathbf{x})^2$



Experiment on 15 prostate cancer patients

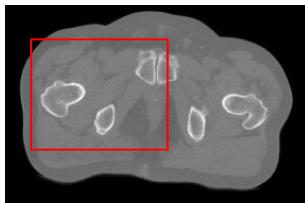
- 3-fold cross-validation for training and testing



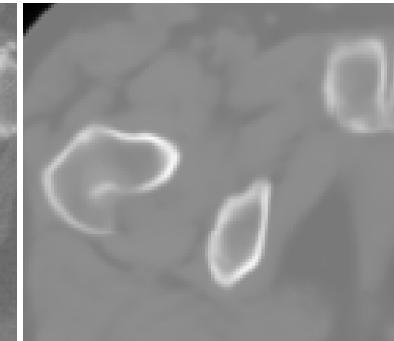
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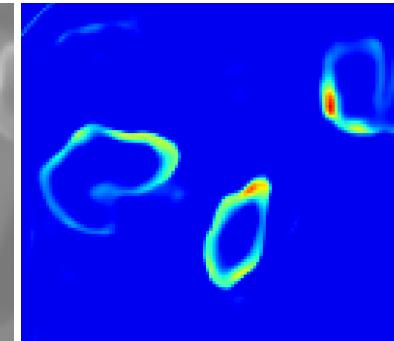
Reference



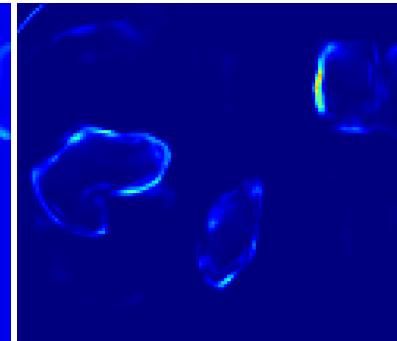
Result



Task uncertainty

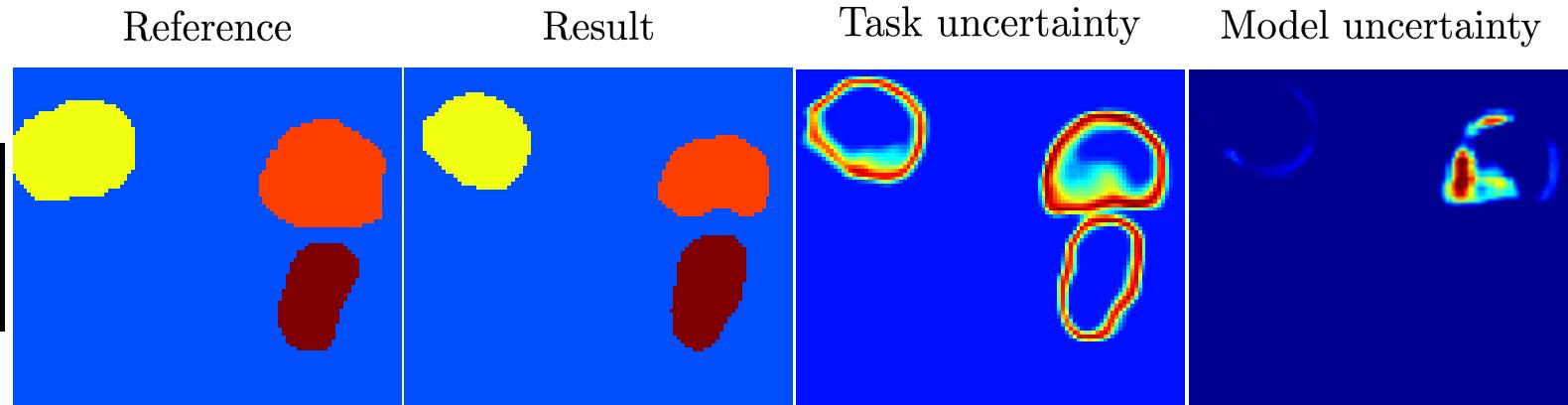


Model uncertainty



Experiment on 15 prostate cancer patients

- 3-fold cross-validation for training and testing

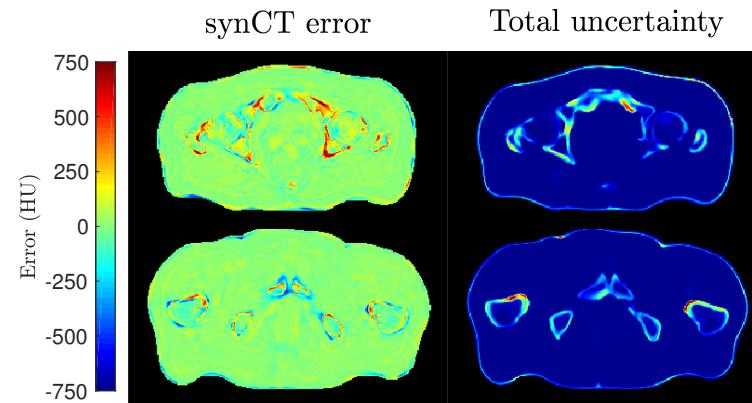


Main results

1. Joint modelling of heteroscedastic uncertainty and test-time variance in a multi-task setting **outperforms** homoscedastic weighting and all other models

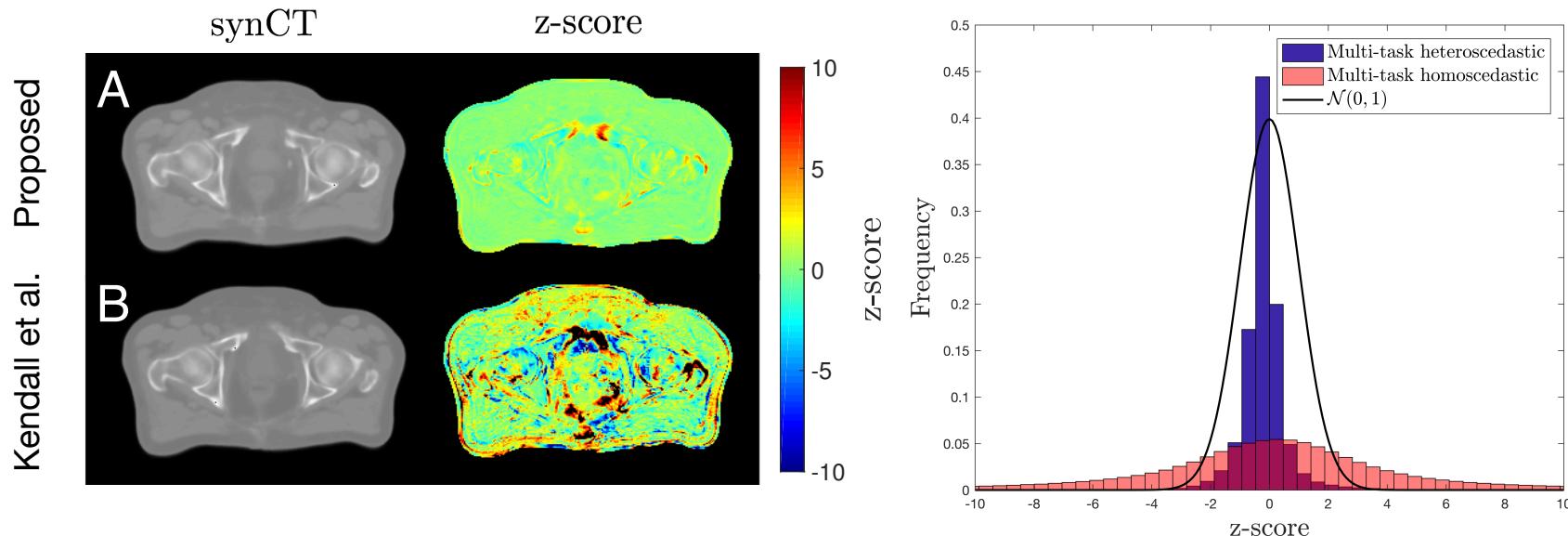
Models	All	Bone	L femur	R femur	Prostate	Rectum	Bladder
	Regression - synCT - Mean Absolute Error (HU)						
Multi-task + homoscedastic weighting	44.3(3.1)	126(14.4)	74.0(19.5)	73.7(17.1)	29.4(4.7)	58.4(48.0)	18.2(3.5)
Our method	43.3(2.9)	121(12.6)	69.7(13.7)	67.8(13.2)	28.9(2.9)	55.1(48.1)	18.3(6.1)

2. Total uncertainty provides a mechanism for automated quality control and assurance



Main results

- Well calibrated variance from our model (**A**) compared those with constant task uncertainty (**B**)

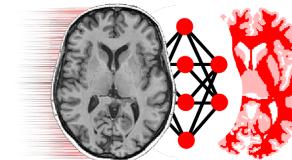


Thanks!

- More results in poster!
- Code to be released within NiftyNet (pip install niftynet)
- Poster #101 tonight from 18:00 to 19:30!



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