

Automating
Treatment
Planning in
Radiation
Therapy

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Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Perelman School of Medicine

University of Pennsylvania, Philadelphia, PA

February 04, 2021

Funding Sources

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT
Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach

Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work



CANCER PREVENTION & RESEARCH
INSTITUTE OF TEXAS

Talk Outline

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Patient Head Motion Correction in External Beam Radiation Therapy
 - Magnetic Resonance Imaging and Linear Accelerator Systems (MRI-LINACs)
 - Intensity-Modulated RT (IMRT): Earlier PhD Work
- Beam Orientation Optimization (BOO)
 - Monte Carlo Tree Search and Neuro-Dynamic Programming for BOO
 - Column Generation as Pretraining for MCTS for BOO
- Robustness Margins and Robust Deep Policies for Nonlinear Control

Research Significance

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Treatment
Planning in
Radiation
Therapy

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Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

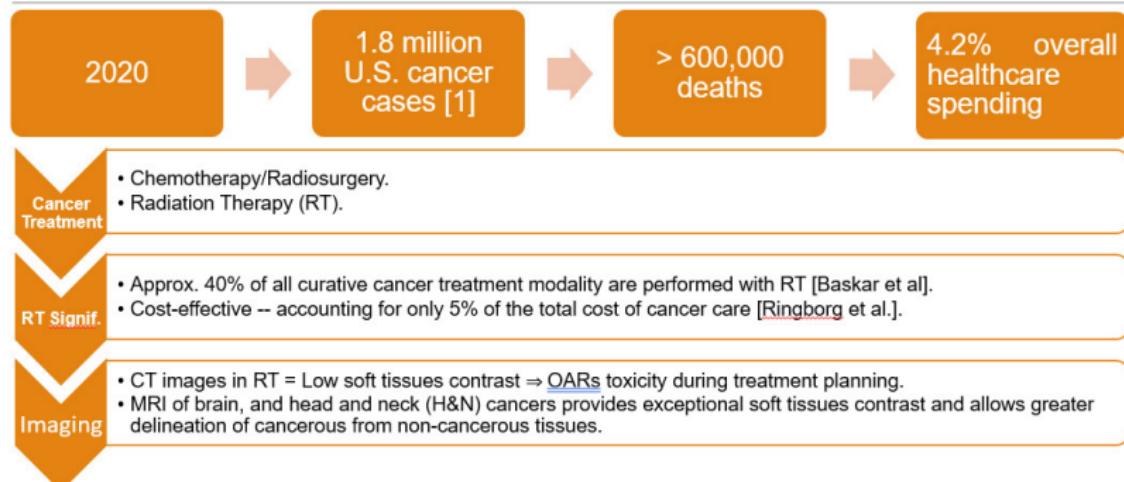
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Robustness issues

Approach

iDG Results

Future Work



IMRT Treatment Planning (Beam Delivery)

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

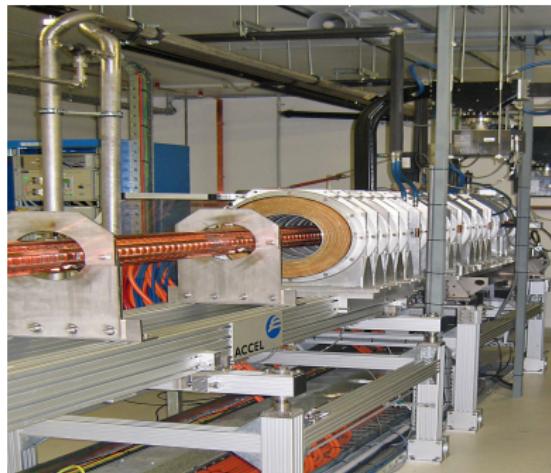
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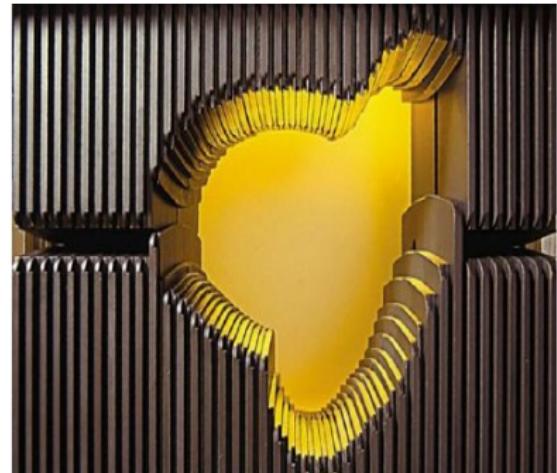
Approach

iDG Results

Future Work



The Australian Synchrotron.



Multi-leaf collimator (Varian)

Radiation Delivery Couch and Gantry

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Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work



Varian's TrueBeam Radiotherapy System.

Head Stabilization in Radiation Therapy (RT)

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Head Stabilization in Cancer Radiation Therapy
 - Intensity-Modulated RT (IMRT): Earlier PhD Work

Simulation Testbed

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Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

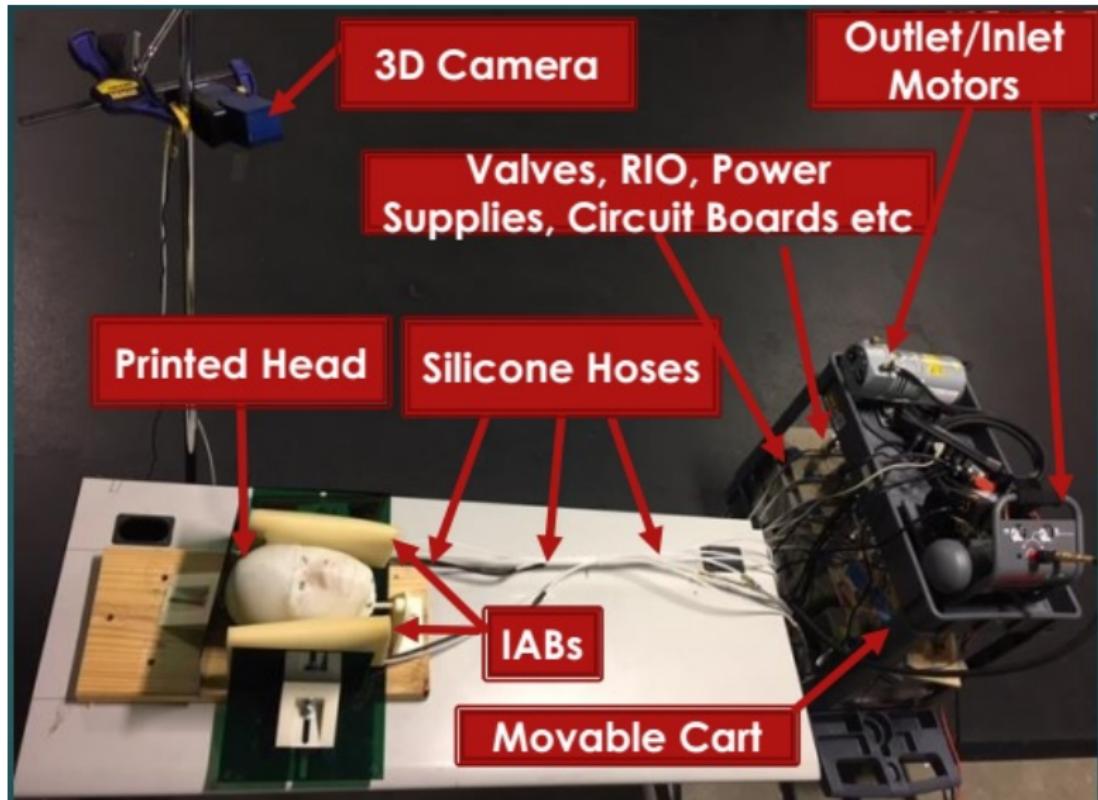
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Robustness issues

Approach

iDG Results

Future Work



Control Design Goals

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation
Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Stabilize z , pitch, and roll states, *i.e.*

$$\mathbf{x} = \begin{pmatrix} z \\ \theta \\ \phi \end{pmatrix}$$

- By solving an adaptive state feedback controller, optimal regulation, and minimize parametric uncertainties

Control Design Goals

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Treatment
Planning in
Radiation
Therapy

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Introduction
IMRT
Neural Network
Architecture

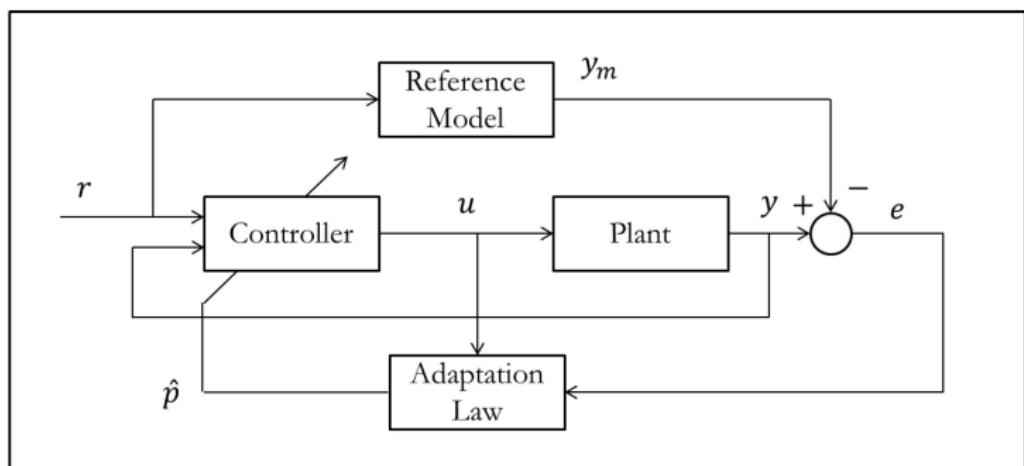
Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

- Provide closed loop tracking given a desired trajectory, r
- Robustify system to (non-)parametric uncertainties



Indirect MRAC system. (Source mdpi.com)

Model Reference Adaptive Control

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Treatment
Planning in
Radiation
Therapy

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Introduction
IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Model head and bladder dynamics as

- $\dot{x} = Ax + B\Lambda(u - f(x, u)) + w(k)$

- Approximate $f(x, u)$ by a neural network with continuous memory states

- Derive adaptive adjustment mechanism from Lyapunov analysis for Adaptive Control Parks (1966)

- $$u = \underbrace{\hat{K}_x^T x}_{\text{state feedback}} + \underbrace{\hat{K}_r^T r}_{\text{optimal regulator}} + \underbrace{\hat{f}(x, u)}_{\text{approximator}}$$

Neural Network Architecture

Automating
Treatment
Planning in
Radiation
Therapy

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Introduction
IMRT
Neural Network
Architecture

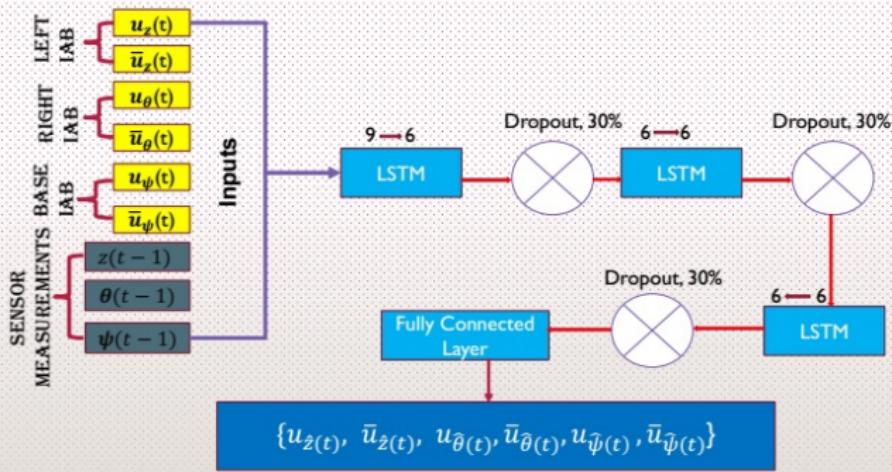
Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

Neural Net Architecture



Lyapunov Redesign: Theorem

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

- For correct adaptive gains, $\hat{\mathbf{K}}_x$ and $\hat{\mathbf{K}}_r$, $\mathbf{e}(k)$ is ***uniformly ultimately bounded***, and the state \mathbf{x} converges to a neighborhood of \mathbf{r} .
- Choose a \mathbf{V} in terms of \mathbf{e} ; $\tilde{\mathbf{K}}_x^T$, $\tilde{\mathbf{K}}_r^T$; and parameter error $\varepsilon_f(\mathbf{x}(k))$ space

$$\mathbf{V}(\mathbf{e}, \tilde{\mathbf{K}}_x, \tilde{\mathbf{K}}_r^T) = \mathbf{e}^T \mathbf{P} \mathbf{e} + \text{tr}(\tilde{\mathbf{K}}_x^T \Gamma_x^{-1} \tilde{\mathbf{K}}_x^T |\Lambda|) + \text{tr}(\tilde{\mathbf{K}}_r^T \Gamma_r^{-1} \tilde{\mathbf{K}}_r^T |\Lambda|)$$

Stability Results: Ogunmolu et al. (2017)

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation
Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

$$\begin{aligned}\dot{\mathbf{V}}(\cdot) &= -\mathbf{e}^T \mathbf{Q} \mathbf{e} - 2\mathbf{e}^T \mathbf{P} \mathbf{B} \boldsymbol{\Lambda} \boldsymbol{\varepsilon}_f \\ &\leq -\lambda_{low} \|\mathbf{e}\|^2 + 2\|\mathbf{e}\| \|\mathbf{P} \mathbf{B}\| \lambda_{high}(\boldsymbol{\Lambda}) \boldsymbol{\varepsilon}_{max}\end{aligned}$$

- $\{\lambda_{low}, \lambda_{high}\} \equiv \min/\max \text{ eigenvalues of } Q \text{ and } \boldsymbol{\Lambda}$.
- $\dot{\mathbf{V}}(\cdot)$ is thus negative definite outside the compact set:
$$\chi = \left(\mathbf{e} : \|\mathbf{e}\| \leq \frac{2\|\mathbf{P} \mathbf{B}\| \lambda_{high}(\boldsymbol{\Lambda}) \boldsymbol{\varepsilon}_{max}(\mathbf{y})}{\lambda_{low}(\mathbf{Q})} \right)$$
 - i.e. \mathbf{e} is uniformly ultimately bounded, or $\mathbf{y}(t) \rightarrow 0$ as $t \rightarrow \infty$.

Results: Z and Pitch Motions

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

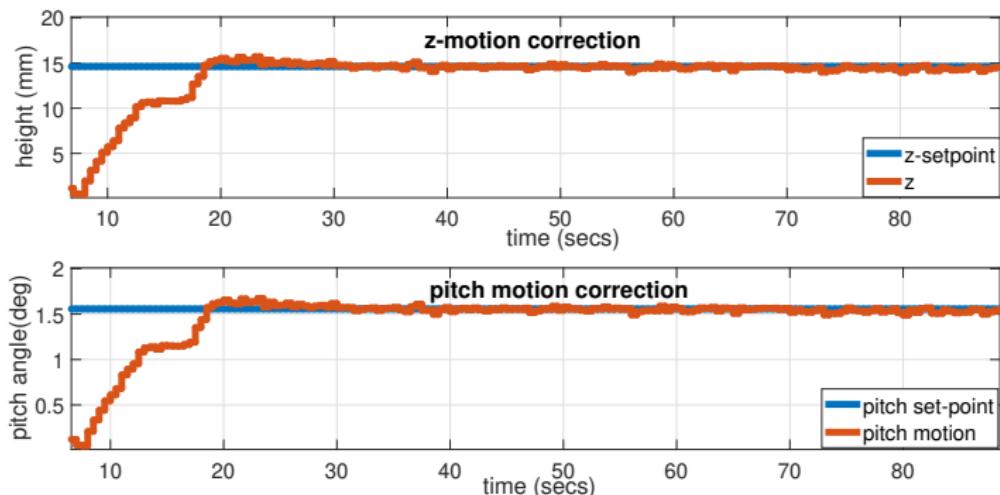
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Approach

iDG Results

Future Work



Goal command: $(z, \theta, \phi) = (14\text{mm}, 1.6^\circ, 45^\circ)^T$.

Results: Roll Motion

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Treatment
Planning in
Radiation
Therapy

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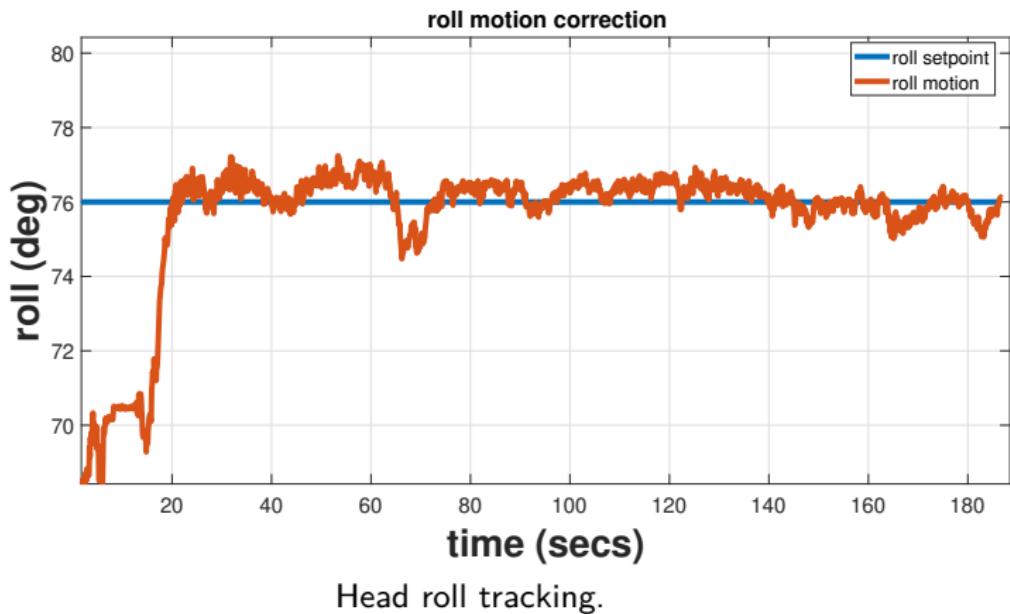
Introduction
IMRT
Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work



Conclusions

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO

MCTS

BOO Motivation
Approach

Column Generation

iDG

Robustness issues
Approach
iDG Results

Future Work

- Non-invasive soft robot for head motion compensation ✓
- Photons-transparent as opposed to rigid/electro-mechanical devices/robots ✓
- Adaptable under MRI coils for newer MRI-LINACs ✓

Head Stabilization in RT

Automating
Treatment
Planning in
Radiation
Therapy

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Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Head Stabilization in Cancer Radiation Therapy
 - Magnetic Resonance Imaging-Linear Accelerator Systems (MRI-LINACs)

Robotic Radiosurgery

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work



A Patient Head Motion-Correction Mechanism for MRI-LINAC RT

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- Current Collaborators: Rodney Wiersma & Xinmin Liu (UChicago → UPenn)
- Past Collaborators: Steve Jiang, Xuejun Gu, (UT Southwestern); Nick Gans (UT Dallas, UT Arlington)

Correcting Head Motion: RT and MRI-LINACs

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Treatment
Planning in
Radiation
Therapy

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Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work



(a) The BRW SRS Frame [Chelvarajah et al. (2004)]



(b) Thermoplastic masks



(c) Frame With MRI Coils (PSOM)

4-D Motion Correction Stage

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Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

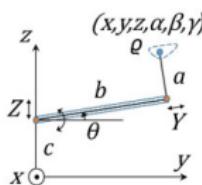
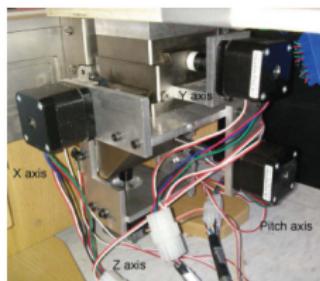
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Approach

iDG Results

Future Work



Liu et al. (2015)

4-DOF Motion Controller Block Diagram

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Planning in
Radiation
Therapy

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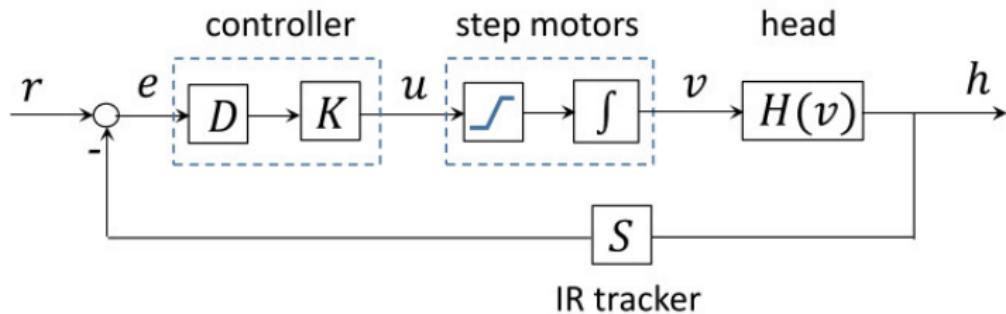
Introduction
IMRT
Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work



Liu et al. (2015)

Phantom Feedback Motion Correction Results

Automating
Treatment
Planning in
Radiation
Therapy

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Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

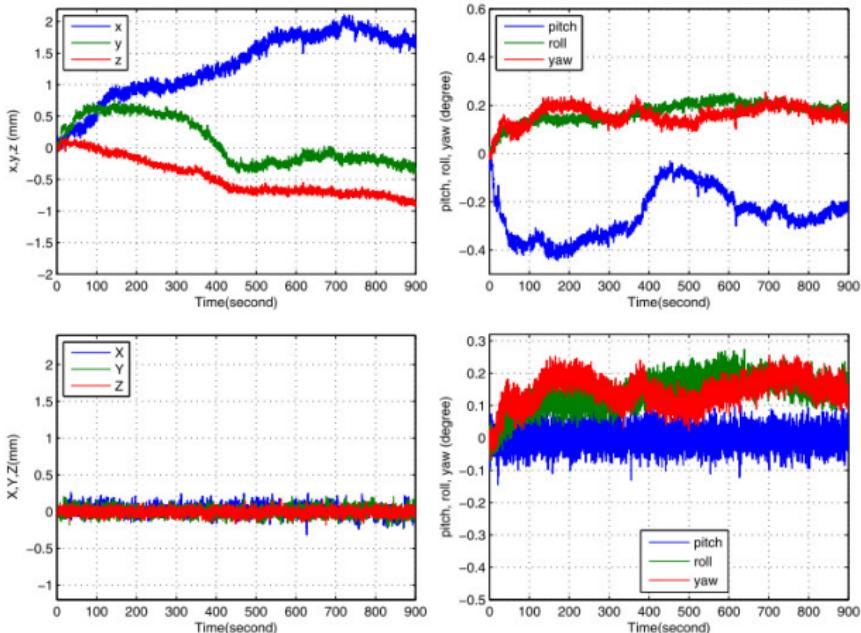
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Approach

iDG Results

Future Work



Time response of feedback control without (left) and with (right) decoupling control [Liu et al. (2015)].

Human Volunteer Feedback Motion Correction Results

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Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

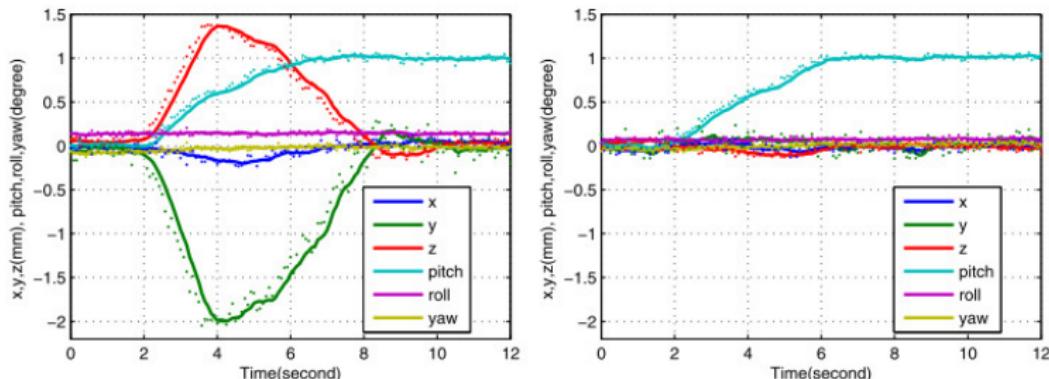
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Approach

iDG Results

Future Work



Head Motion Without and With Motion Correction. Left: Coupled Axes; Right: Decoupled Axes.

SRS: Wiersma Stewart-Gough Platform

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Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

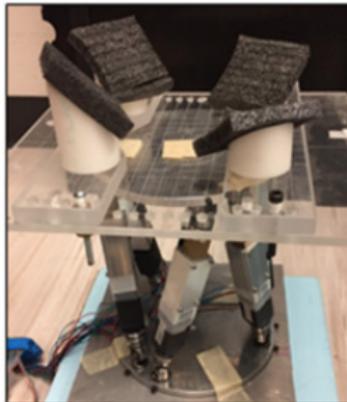
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Robustness issues

Approach

iDG Results

Future Work



6-DOF Motion Correction Results

Automating
Treatment
Planning in
Radiation
Therapy

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Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

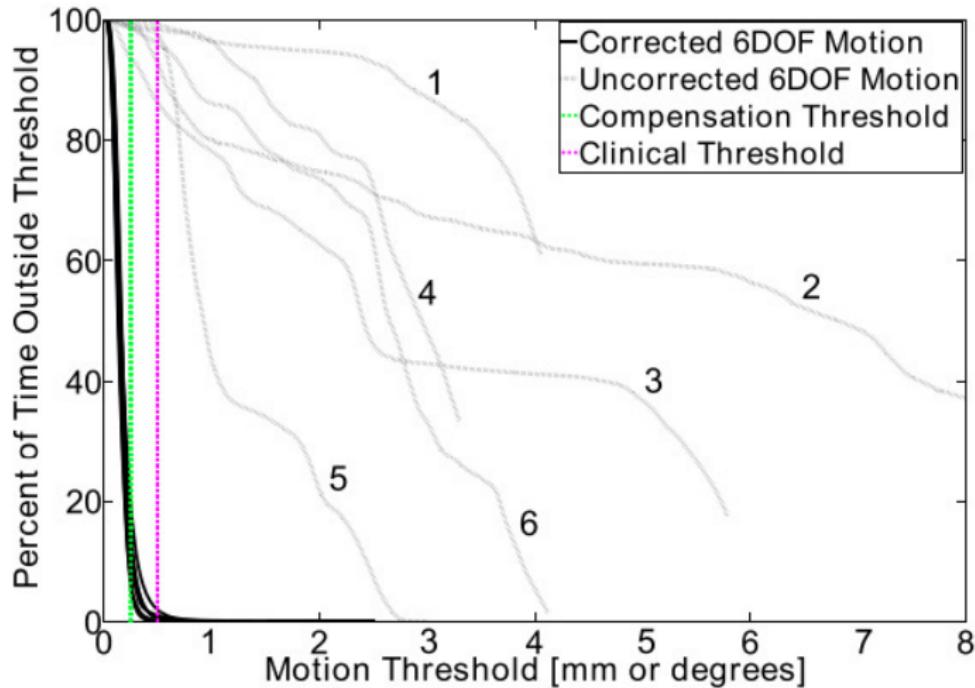
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Robustness issues

Approach

iDG Results

Future Work



Next-Gen RT Treatment with MRI-LINACs

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work



Elekta's Unity MRI-LINAC.



MagnetTx



MRIDIAN by ViewRay: MR image guidance Radiation on table Adaptive Radiotherapy.



MRI in LINAC RT

- Next generation precision beam delivery.
 - High speed, high resolution MLC.
 - Online plan adaptation capabilities.
-
- MRI that offers superior soft tissues visualization integrated with linear accelerator (LINAC) RT Offers univiewed, online, and real-time cancer RT treatment [Raaymakers et al., Raaymakers et al.]
 - Commercialized in systems such as
 - Elekta AB's (Sweden) 1.5T diagnostic imaging system [Raaymakers et al.];
 - Viewray's MRIdian system [Motic et al.]; or
 - the MagnetTx's (Canada) Aurora RT system [Fallone et al.] among others.
 - Random and involuntary patient motion often occurs during image acquisition leading to
 - Artifacts → Poor image quality.
 - Incomplete irradiation of the tumor target.
 - Exposure of healthy tissues to radiation toxicity.
 - ❖ These lower the accuracy of online and real-time precise radiation dose delivery.
 - ❖ Affects clinical efficacy.

Pneumatic Actuated Soft Robots for Head Motion Compensation

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Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

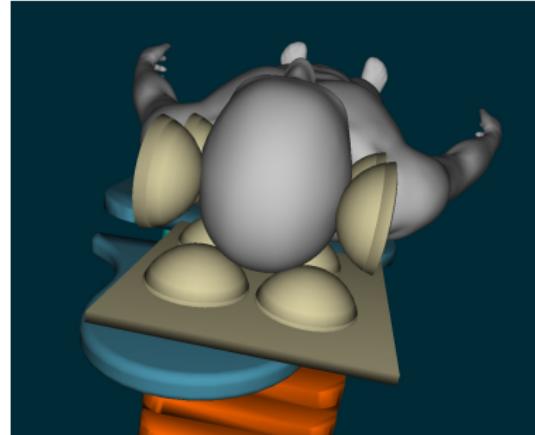
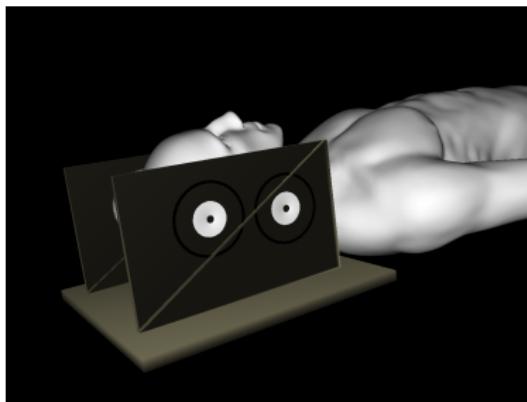
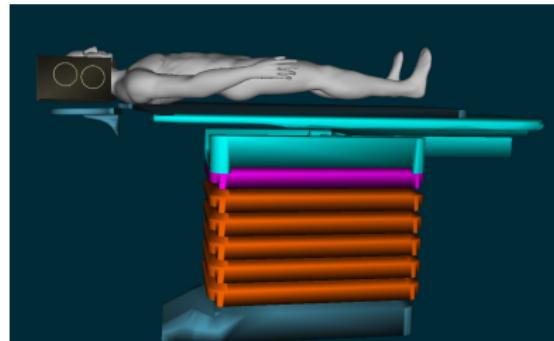
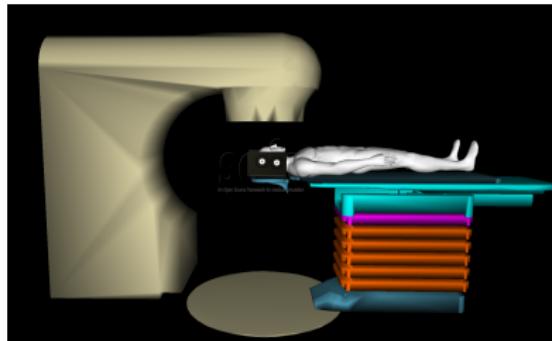
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Robustness issues

Approach

iDG Results

Future Work



Cephalopods-inspired CCOARSE Actuator Design

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

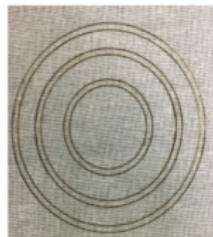
Robustness issues

Approach

iDG Results

Future Work

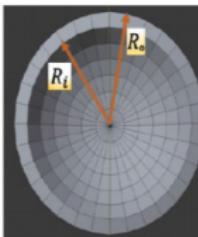
Circumferentially Constrained And Radially Symmetric Elastomers [Pikul et al. (2019)].



(a) Laser-Cut Fiber



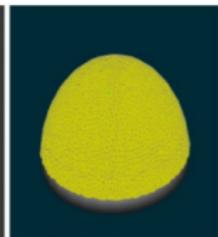
(b) Fiber+Rubber



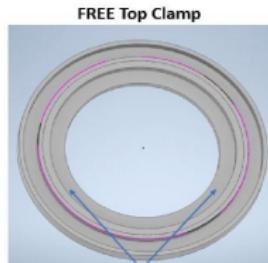
(c) Deformation Model



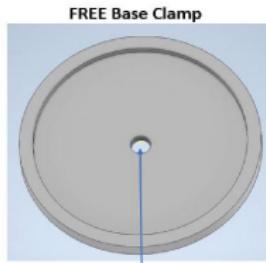
(d) Actuator+PVC Base



(e) Finite Element Model

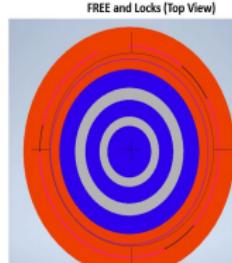


FREE Top Clamp

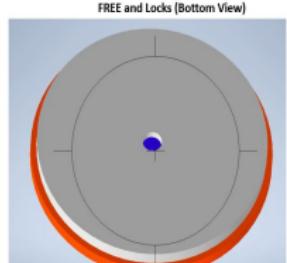


FREE Base Clamp

(f,g)



FREE and Locks (Top View)



(h)

CCOARSE Actuator Schematic

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Treatment
Planning in
Radiation
Therapy

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Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

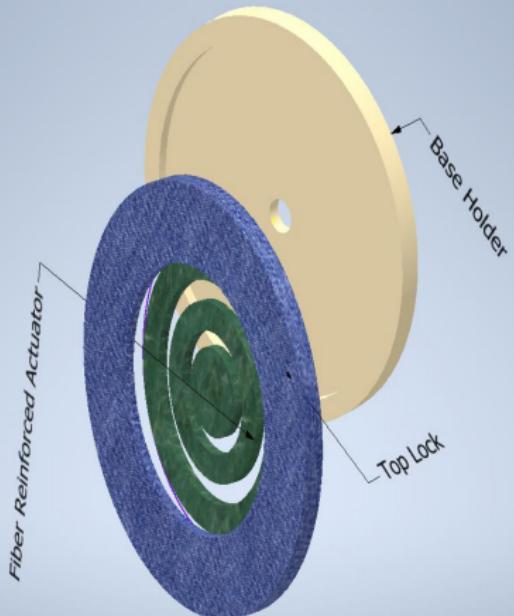
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Robustness issues

Approach

iDG Results

Future Work



Nonlinear Elastic Deformation Analysis

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Treatment
Planning in
Radiation
Therapy

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Introduction
IMRT
Neural Network
Architecture

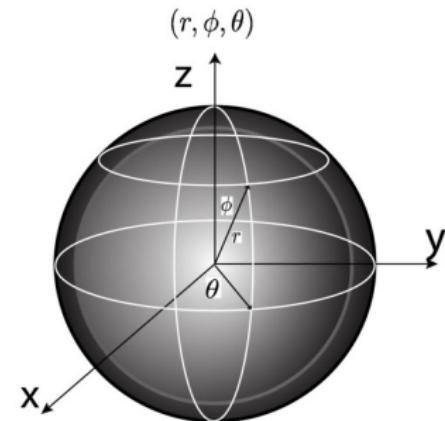
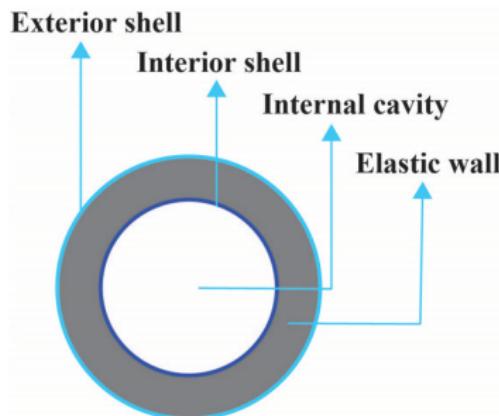
Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

IAB SHELLS AND AIR CAVITY/DEFORMATION ANALYSIS



$$r_i \leq r \leq r_o, \quad 0 \leq \theta \leq 2\pi, \quad 0 \leq \phi \leq \pi$$

Soft IK via Boundary Value Problem

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS
BOO Motivation
Approach

Column Generation

iDG

Robustness issues
Approach
iDG Results

Future Work

- Using the following boundary conditions for the Cauchy Stress,
 - $\sigma_{rr}|_{R=R_0} = -P_{atm}, \sigma_{rr}|_{R=R_i} = -P_{atm} - P$
- And together with Cauchy's first law, we find that
 - $\sigma_{rr}(r) = - \int_{r_i}^{r_o} [2C_1\left(\frac{r}{R^2} - \frac{R^4}{r^5}\right) + 2C_2\left(\frac{r^3}{R^4} - \frac{R^2}{r^3}\right)] dr$
 - $\sigma_{rr}(r) = \int_{R_i}^{R_o} [2C_1\left(\frac{1}{r} - \frac{R^6}{r^7}\right) - 2C_2\left(\frac{R^4}{r^5} - \frac{r}{R^2}\right)] dr$
- With $\sigma_{rr}|_{R=R_i} = -P_{atm} - P$ and setting $P_{atm} = 0$, we find
 - $P(r) = \int_{r_i}^{r_o} [2C_1\left(\frac{r}{R^2} - \frac{R^4}{r^5}\right) + 2C_2\left(\frac{r^3}{R^4} - \frac{R^2}{r^3}\right)] dr$
 - $P(r) = \int_{R_i}^{R_o} [2C_1\left(\frac{1}{r} - \frac{R^6}{r^7}\right) - 2C_2\left(\frac{R^4}{r^5} - \frac{r}{R^2}\right)] dr$
 - $r^3 = R^3 + r_i^3 - R_i^3 \text{ and } r_o^3 = R_o^3 + r_i^3 - R_i^3$

Volumetric Deformation Results (Simulation)

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

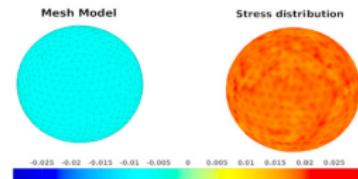
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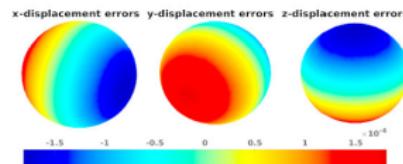
Approach

iDG Results

Future Work



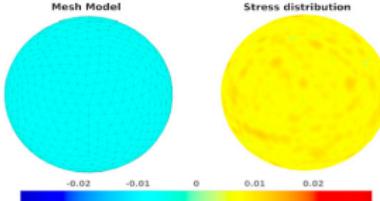
(a) Left: Mesh model. Right: Stress distribution on outer skin.



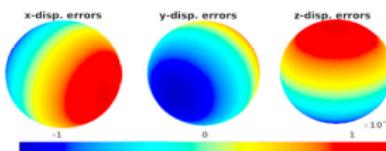
(b) Displacement errors along x, y, z coordinates.

Inputs				Outputs			
C_1	C_2	R_i	r_i	R_o	r_o	P	ΔV
1.1e4	2.2e4	.027	.03	.03	.033	.76	≈ 0

Fig. 6: Volumetric Deformation (Expansion).



(a) Left: Mesh model. Right: Stress distribution on outer skin.



(b) Displacement errors along x, y, z coordinates.

Inputs				Outputs			
C_1	C_2	R_i	r_i	R_o	r_o	P	ΔV
1.1e4	2.2e4	.025	.03	.03	.028	-.34	≈ 0

Fig. 7: Volumetric Deformation (Compression).

Pneumatic Control and Deformation Scheme

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

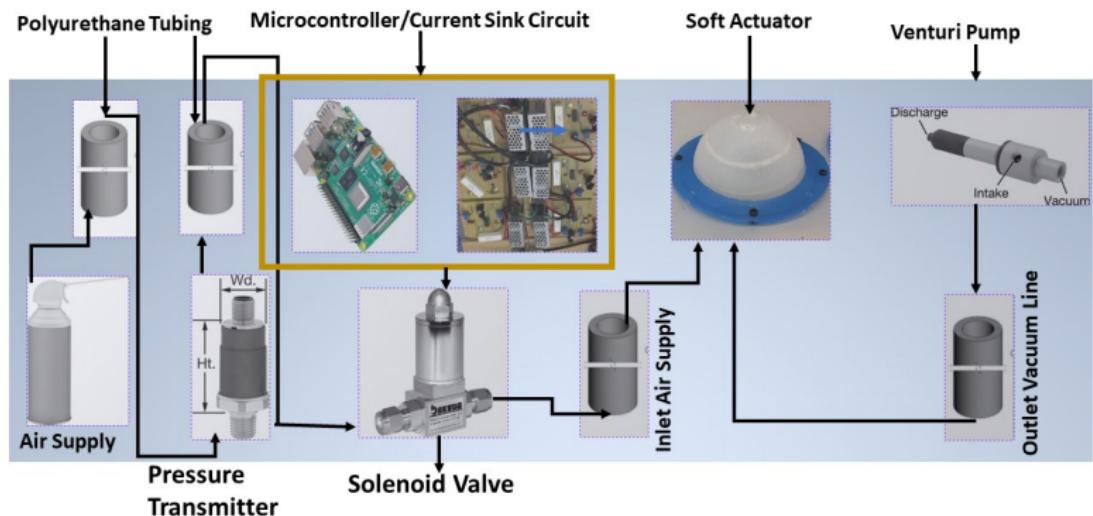
iDG

Robustness issues

Approach

iDG Results

Future Work



Volumetric Deformation Results (Actual)

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

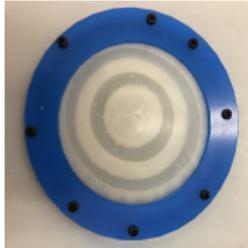
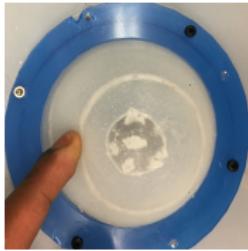
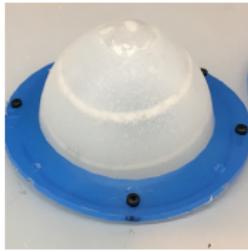
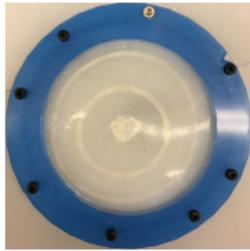
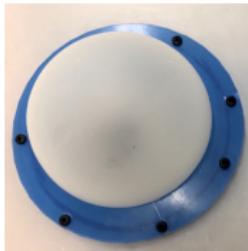
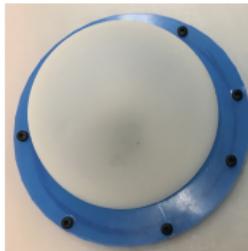
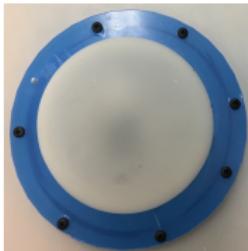
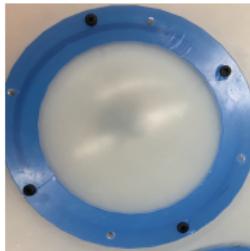
iDG

Robustness issues

Approach

iDG Results

Future Work



Head Motion Control (Independent Actuation)

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

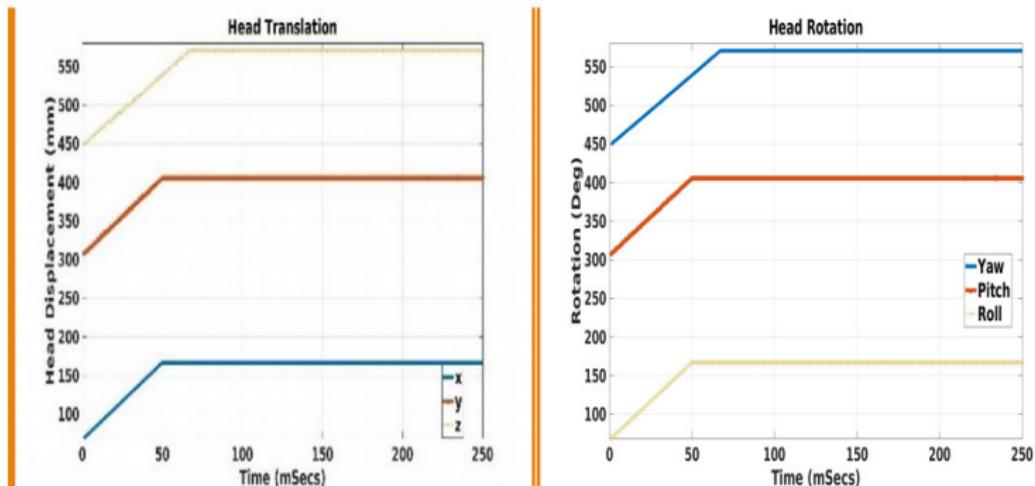
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Robustness issues

Approach

iDG Results

Future Work



Head Translation along x, y, z for a task of raising the head by a certain threshold above the table

Head rotation in Euler angles for a task of tilting the head about the x, y, z axes on the treatment table.

Ongoing Work

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

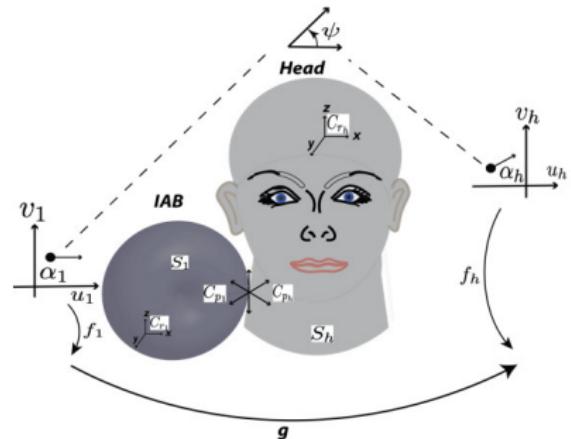
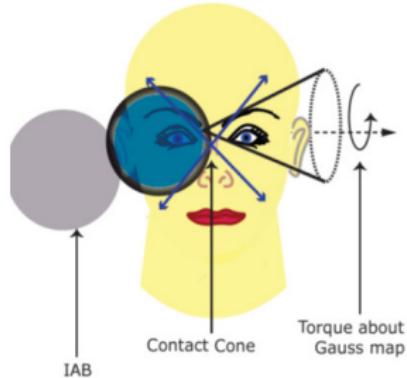
Robustness issues

Approach

iDG Results

Future Work

Continuum Mechanical Model Validation/Differential Geometry/Newton-Euler Dynamics



Part I.A: Beam Orientation Optimization (BOO)

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

■ Beam Orientation Optimization (BOO)

■ Monte Carlo Tree Search and Neuro-Dynamic Programming for BOO

BOO Relevant Works

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Sadeghnejad Barkousaraie, Azar, **Olalekan Ogunmolu**, Steve Jiang, and Dan Nguyen. "A fast deep learning approach for beam orientation optimization for prostate cancer treated with intensity-modulated radiation therapy." In *Medical physics: International Journal of Medical Physics Research and Practice*, 47, no. 3 (2020): 880-897.
- **Ogunmolu, Olalekan**, Michael Folkerts, Dan Nguyen, Nicholas Gans, and Steve Jiang. "Deep BOO! Automating Beam Orientation Optimization in Radiation Therapy." In *Algorithm Foundations of Robotics XIII*, Merida, Mexico. Published in *Springer's Proceedings in Advanced Robotics (SPAR) Book*, 2020.
- Barkousaraie, Azar Sadeghnejad, **Olalekan Ogunmolu**, Steve Jiang, and Dan Nguyen. "Using Supervised Learning and Guided Monte Carlo Tree Search for Beam Orientation Optimization in Radiation Therapy." In *Workshop on Artificial Intelligence in Radiation Therapy*, pp. 1-9. Springer, Cham, 2019.
- Azar Sadeghnejad Barkousaraie, **Olalekan Ogunmolu**, Steve Jiang, and Dan Nguyen. "A Fast Deep Learning Approach for Beam Orientation Selection Using Supervised Learning with Column Generation on IMRT Prostate Cancer Patients." *Medical Physics (AAPM)* 46 (6), E237-E237, San Antonio, TX, July 2019.
- **Olalekan Ogunmolu**, Azar Sadeghnejad Barkousaraie, Nicholas Gans, Steve Jiang, and Dan Nguyen. "An Approximate Policy Iteration Scheme for Beam Orientation Selection in Radiation Therapy." *Medical Physics (AAPM)* 46 (6), E386-E386 San Antonio, TX, July 2019.
- Azar Sadeghnejad Barkousaraie, **Olalekan Ogunmolu**, Steve Jiang, and Dan Nguyen. "A Reinforcement Learning Application of Guided Monte Carlo Tree Search Algorithm for Beam Orientation Selection in Radiation Therapy." *Medical Physics (AAPM)* 46 (6), E236-E236, San Antonio, TX, July 2019.

Contributions

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS

BOO Motivation
Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

Relevant Publications

Ogunmolu, Olalekan, Michael Folkerts, Dan Nguyen, Nicholas Gans, and Steve Jiang. "Deep BOO! Automating Beam Orientation Optimization in Radiation Therapy." In *Algorithm Foundations of Robotics XIII*, Merida, Mexico. Published in *Springer's Proceedings in Advanced Robotics (SPAR) Book*, 2020.

- A sparse tree lookout strategy for games with large state spaces guides transition between beam angle sets
- Tree lookout strategy guided by a deep neural network policy

BOO Process: Fluence Map Optimization

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

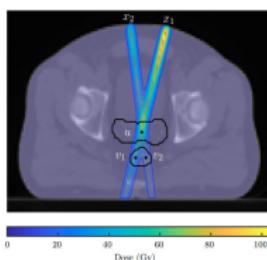
Approach

iDG Results

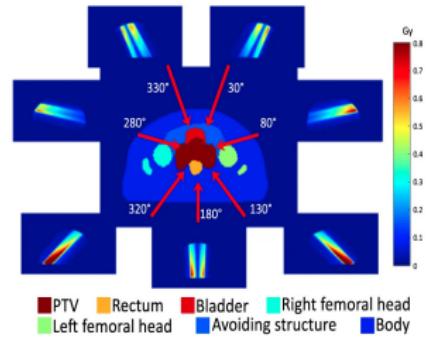
Future Work



Prostate CT slice



Prostate before
BOO



Fluence Map

Treatment Plan Flowchart

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Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

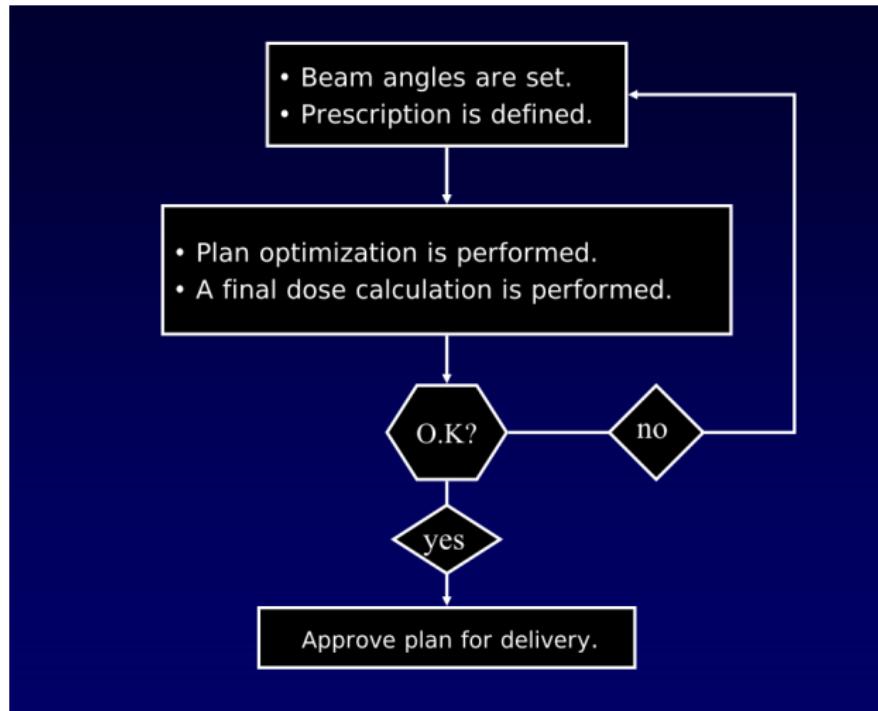
iDG

Robustness issues

Approach

iDG Results

Future Work



Reprinted from "IMRT Optimization Algorithms. David Shepard. Swedish Cancer Institute. AAPM 2007."

Current Approaches

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

- Stochastic optimization approaches: simulated annealing; genetic algorithms and gradient search, or a combination of genetic and gradient search algorithms.
- Mixed-integer programming, branch and cut/bound algorithms, beam angle elimination algorithms.
- Commercial planners use some highly non-convex objective (actual function is proprietary and unknown to public).

IMRT/BOO Motivation

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT
Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

- Beam orientations largely manually chosen or adopted from a standard protocol for clinical use.
- Pre-solve the dose influence matrices for each beam orientation.
- Then solve FMO.
- Time consuming (hours for dose fluence), and minutes for (FMO); Still solution is often not optimal.

Approach

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO

MCTS

BOO Motivation
Approach
Column Generation

iDG

Robustness issues
Approach
iDG Results

Future Work

- A Tower Neural Network generates a policy that guides MCTS simulations for two players in a zero-sum Markov game
 - Produces a *utility (value) function* & a subjective *probability distribution*
- Each player in a two-player Markov game finds an alternating best response to the current player's average strategy
 - driving the neural network policy's weights toward an approximate **saddle equilibrium** [Heinrich et al. (2015)].
 - aids network in finding an *approximately optimal* beam angle candidate set that meets a dosimetric requirements.

Data Preprocessing

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- 77 anonymized patient CT scans, D , and their dose influence matrices, \mathcal{D}_{ij}
- Scans shaped, $D \times N \times H \times W$ from prostate cases in previous treatment plans
- Each slice resized to 64×64

State Representation: Prostate Organ Masks

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

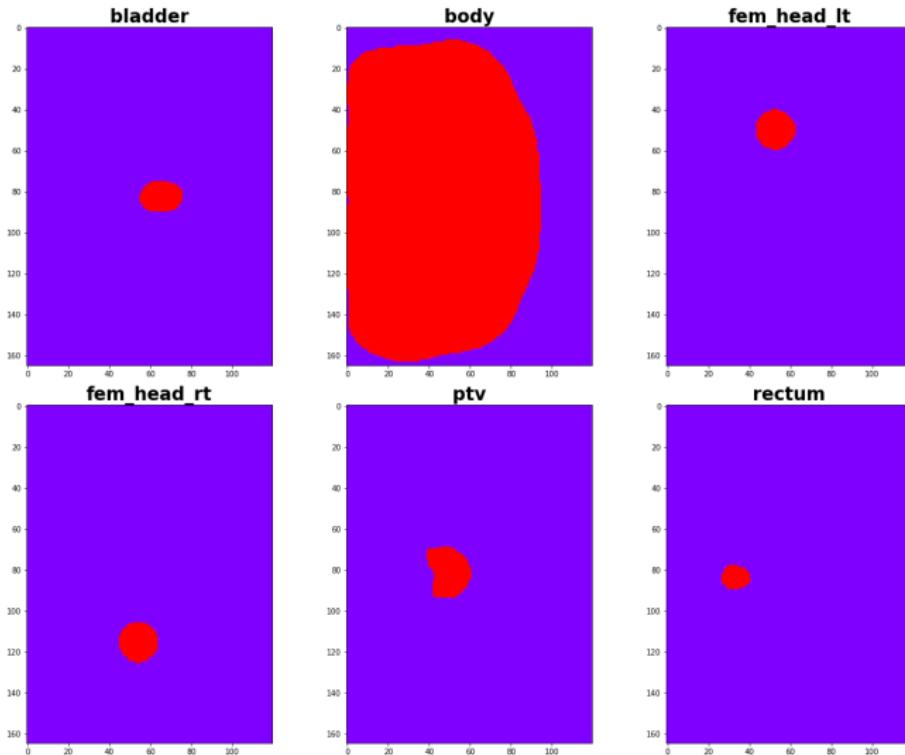
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Robustness issues

Approach

iDG Results

Future Work



State Representation: Beam Angles

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

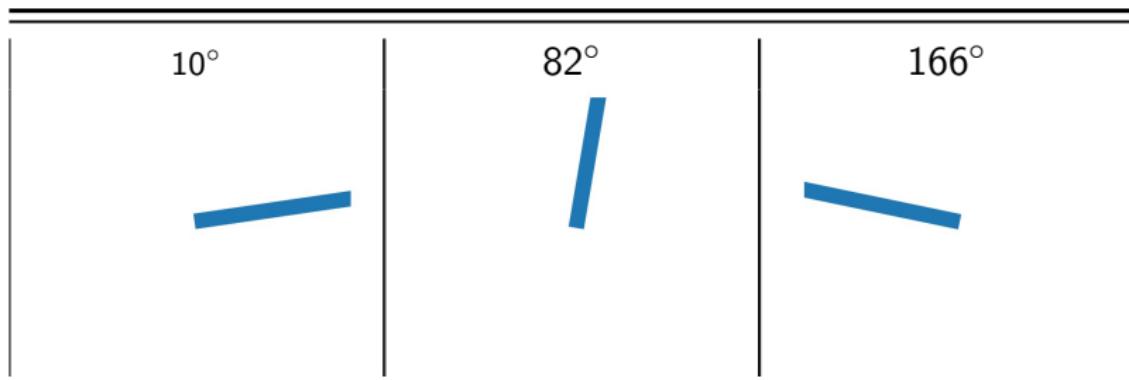
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Robustness issues

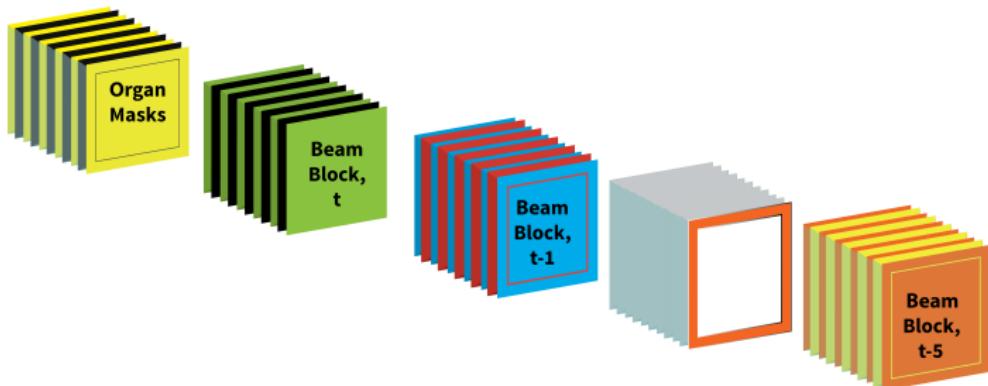
Approach

iDG Results

Future Work



State Representation



State Representation

Automating Treatment Planning in Radiation Therapy

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Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

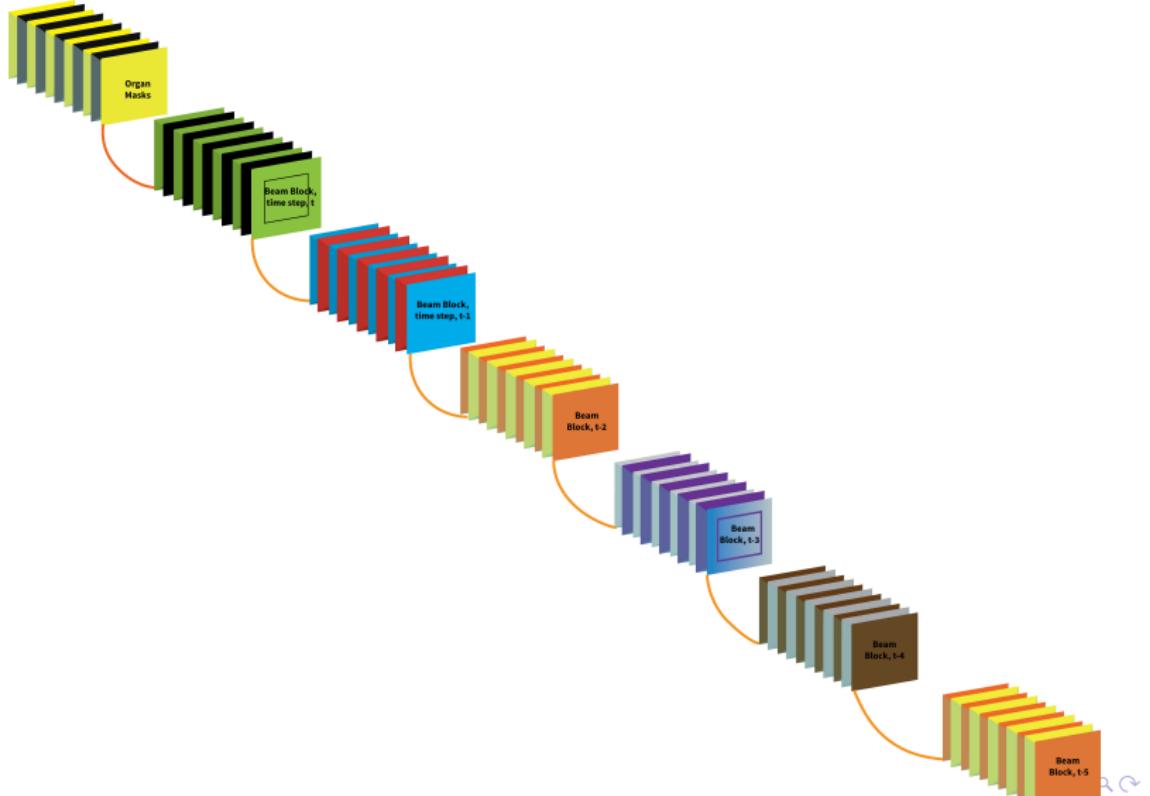
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Robustness issues

Approach

iDG Results

Future Work



Tree Representation and Game Simulation

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

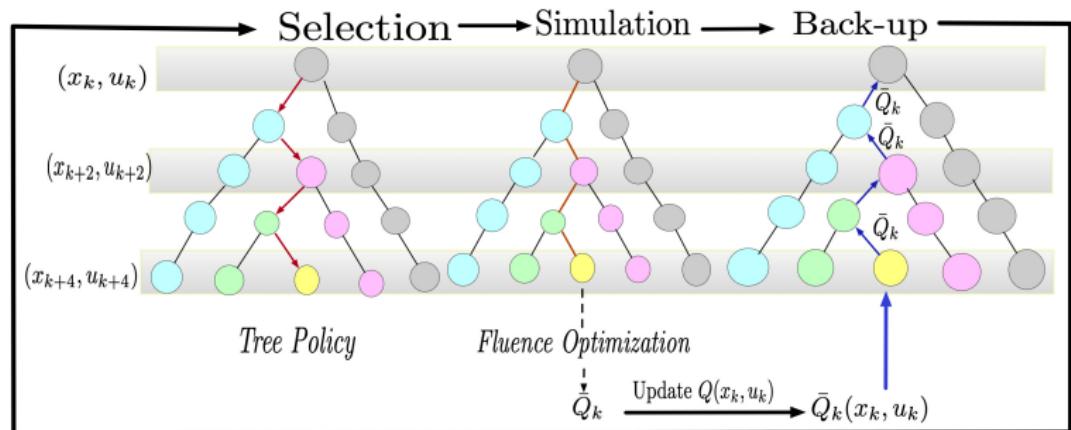
iDG

Robustness issues

Approach

iDG Results

Future Work



Tree Composition

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT
Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

Every **node** of the tree, \mathbf{x} , has the following fields:

- a pointer to the parent that led to it, $\mathbf{x}.p$;
- the beamlets, \mathbf{x}_b , stored at that node; $b = \{1, \dots, m\}$;
- a set of move probabilities prior, $p(s, a)$;
- a pointer $\mathbf{x}.r$, to the reward r_t , for the state \mathbf{x}_t ;
- a pointer to the state-action value $Q(s, a)$ and its upper confidence bound $U(s, a)$;
- a visit count $N(s, a)$, that indicates the number of times that node was visited; and
- a pointer $\mathbf{x}.child$; to each of its children nodes.

Game Simulation: Mixed Strategies

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO

MCTS

BOO Motivation
Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Each player, p_1, p_2 , bases its decision on a random event's outcome
 - generating a **mixed strategy** determined by **averaging the outcome** of individual plays.
- Both players constitute a two-player **stochastic action selection strategy**: $\pi(s, a) = Pr(a|s) := \{\pi^{p_1}, \pi^{p_2}\}$ that gives the probability of selecting moves in any given state
- Suppose the game simulation starts from an initial condition s_0 .

Saddle Point Strategy Formulation

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT
Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS
BOO Motivation
Approach
Column Generation

iDG

Robustness issues
Approach
iDG Results

Future Work

- The **saddle point strategies** for an optimal control sequence pair $\{a_t^{p_1^*}, a_t^{p_2^*}\}$ can be recursively obtained by optimizing a state-action value cost, $\mathcal{J}_t(s, a)$

$$V_t^*(s) = Q_t^*(s_t, \pi_t^{p_1}, \pi_t^{p_2}) = \min_{\pi^{p_1} \in \Pi^{p_1}} \max_{\pi^{p_2} \in \Pi^{p_2}} Q_t^*(s_t, \pi^{p_1}, \pi^{p_2}) \\ \forall s_t \in \mathcal{S}, \pi^{p_1} \in \Pi^{p_1}, \pi^{p_2} \in \Pi^{p_2}.$$

such that

$$v_{p_1}^* \leq v^* \leq v_{p_2}^* \quad \forall \{\pi_t^{p_1}, \pi_t^{p_2}\}_{0 \leq t \leq T}.$$

where $v_{p_i}^*$ are the respective optimal values for each player.

Fluence Map Optimization

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- $\mathcal{X} \implies$ total discretized voxels of interest (*VOI's*) in a target volume
- $\mathcal{B}_1 \cup \mathcal{B}_2 \cup \dots \cup \mathcal{B}_n \subseteq \mathcal{B} \implies$ beam partition subset
- $\mathcal{D}_{ij}(\theta_k) \implies$ matrix that describes each dose influence, d_i
 - Computed by calculating each d_i for every bixel, j , at every φ° , resolution, where $j \in \mathcal{B}_k$

Methods: FMO problem definition

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

■ Cost

$$\frac{1}{v_s} \sum_{s \in \text{OARs}} \|(\underline{b}_s - \underline{w}_s \mathcal{D}_{ij}^s \mathbf{x}_s)_+\|_2^2 + \frac{1}{v_s} \sum_{s \in \text{PTVs}} \|(\bar{w}_s \mathcal{D}_{ij}^s \mathbf{x}_s - b_s)_+\|_2^2 \quad (1)$$

■ Pre-calculated dose term: $\mathbf{A}\mathbf{x} = \{\sum_s \frac{w_s}{v_s} \mathcal{D}_{ij}^s \mathbf{x}_s \mid \mathcal{D}_{ij} \in \mathbb{R}^{n \times l}, n > l\}$

Methods: FMO

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Rewriting the objective

$$\min \frac{1}{2} \|Ax - b\|_2^2 \quad \text{subject to } x \geq 0.$$

- With Lagrangian:

$$L(x, \lambda) = \min \frac{1}{2} \|Ax - b\|_2^2 - \lambda^T x.$$

- Introducing an auxiliary variable z , we have

$$\min_x \frac{1}{2} \|Ax - b\|_2^2, \quad \text{subject to } z = x, \quad z \geq 0,$$

Methods: FMO by way of ADMM

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation
Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Solving either the \mathbf{x} and \mathbf{z} sub-problems, we have

$$\mathbf{x}^{k+1} = (\mathbf{A}^T \mathbf{A} + \rho \mathbf{I})^{-1} (\mathbf{A}^T \mathbf{b} + \rho \mathbf{z}^k - \boldsymbol{\lambda}^k). \quad (2)$$

- And using the soft-thresholding operator, $S_{\boldsymbol{\lambda}/\rho}$, we find that

$$\mathbf{z}^{k+1} = S_{\boldsymbol{\lambda}/\rho} (\mathbf{x}^{k+1} + \boldsymbol{\lambda}^k), \quad (3)$$

where $S_{\boldsymbol{\lambda}/\rho}(\tau) = (\mathbf{x} - \boldsymbol{\lambda}/\rho)_+ - (-\tau - \boldsymbol{\lambda}/\rho)_+$. $\boldsymbol{\lambda}$ is updated as

$$\boldsymbol{\lambda}^{k+1} = \boldsymbol{\lambda}^k - \gamma (\mathbf{z}^{k+1} - \mathbf{x}^{k+1}), \quad (4)$$

where γ is a parameter that controls the step length.

BOO Results: Testing of self-play network

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

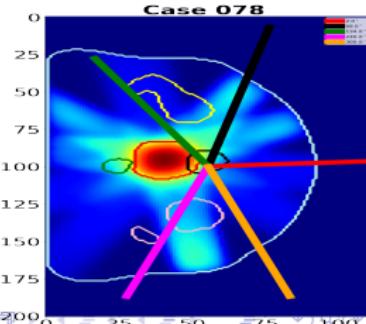
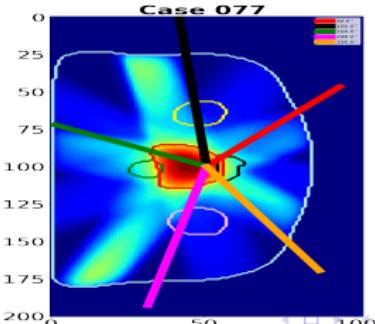
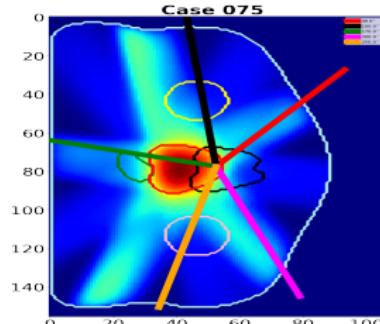
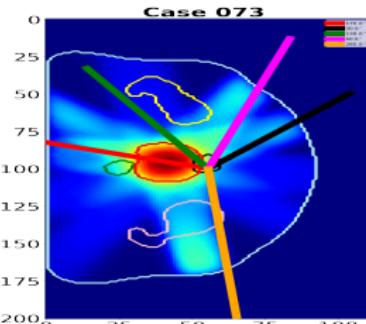
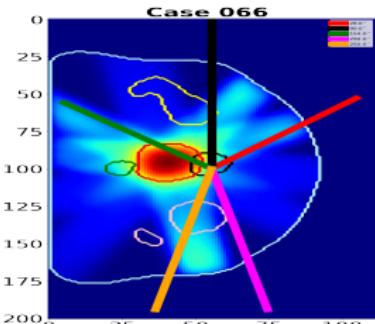
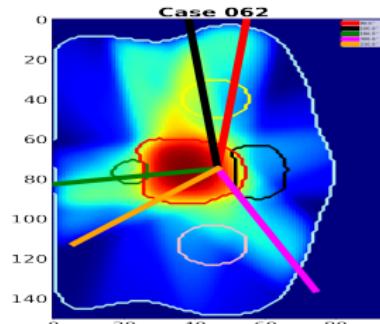
Robustness issues

Approach

iDG Results

Future Work

Inference Regime



Part I.B: Supervised Column Generation Pretraining for BOO

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction
IMRT
Neural Network Architecture

Head Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

■ Beam Orientation Optimization (BOO)

- Monte Carlo Tree Search and Neuro-Dynamic Programming for BOO
- → Column Generation as Pretraining for Deep Neural Network BOO

Relevant Publication

- Sadeghnejad Barkousaraie, Azar, Olalekan Ogunmolu, Steve Jiang, and Dan Nguyen. "A fast deep learning approach for beam orientation optimization for prostate cancer treated with intensity-modulated radiation therapy." In *Medical physics: International Journal of Medical Physics Research and Practice*, 47, no. 3 (2020): 880-897.

Column Generation as Pretraining for DNN

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

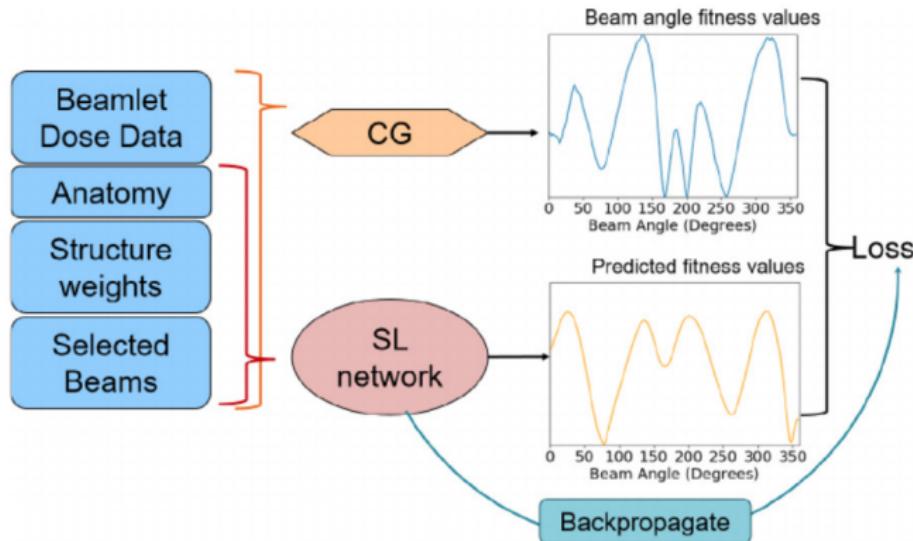
iDG

Robustness issues

Approach

iDG Results

Future Work



Network Structure

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

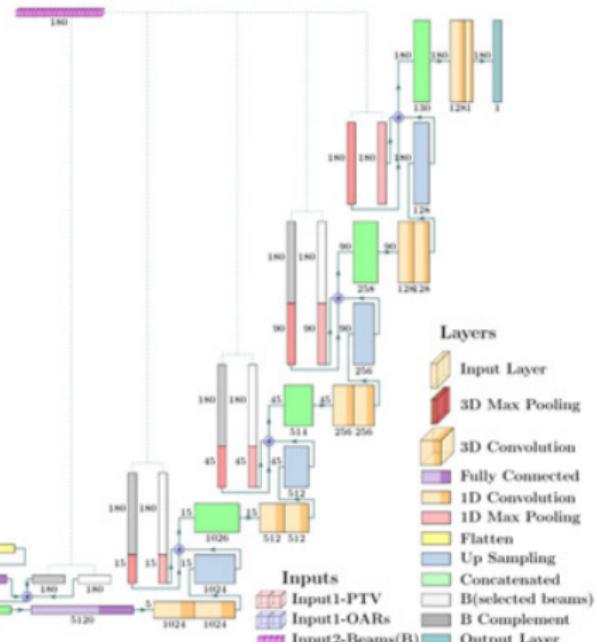
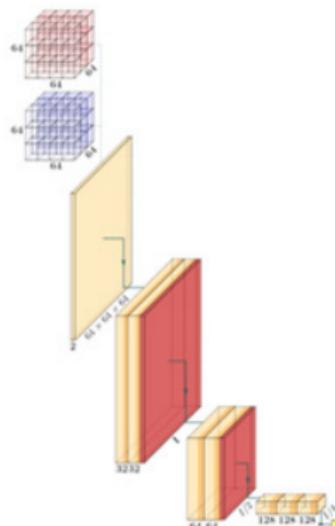
iDG

Robustness issues

Approach

iDG Results

Future Work



Training and Validation Loss

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

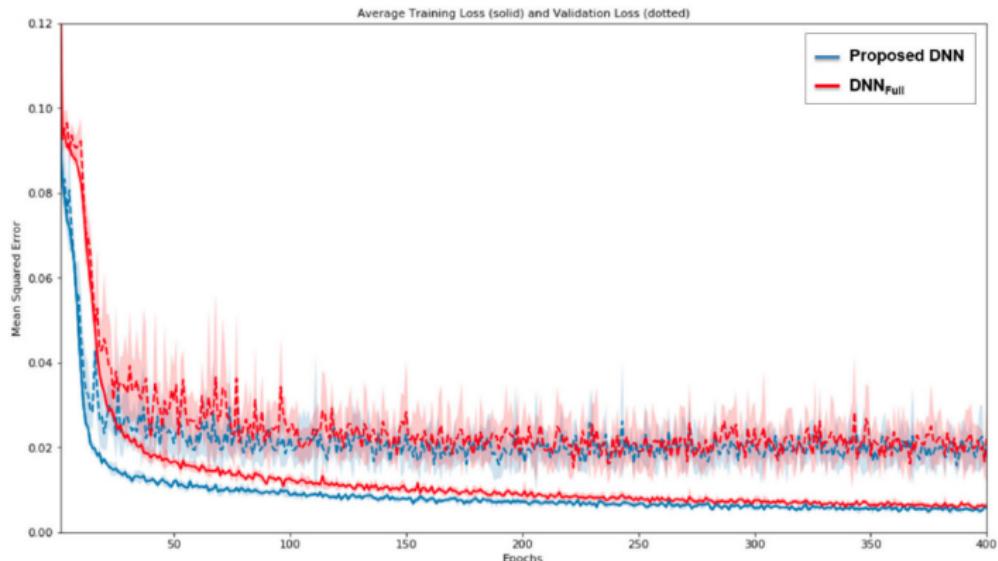
iDG

Robustness issues

Approach

iDG Results

Future Work



Average training (solid) and validation (dotted) loss function (MSE) values across six cross-validation folds for the network (blue) and full network.

Inference: Column Generation vs U-Net

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

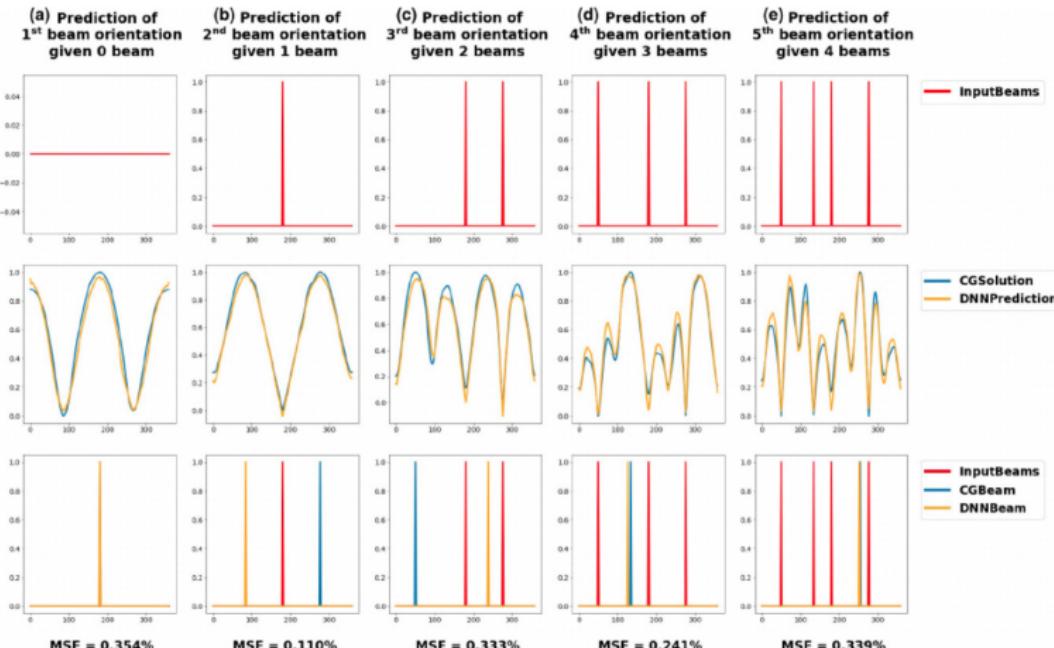
iDG

Robustness issues

Approach

iDG Results

Future Work



- Prediction of 1st beam orientation given no beam.
- Prediction of 2nd beam orientation given 1 beam.
- Prediction of 3rd beam orientation given 2 beams.
- Prediction of 4th beam orientation given 3 beams.
- Prediction of 5th beam orientation given 4 beams.

Dose Washes of Column Generation vs Neural Network

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

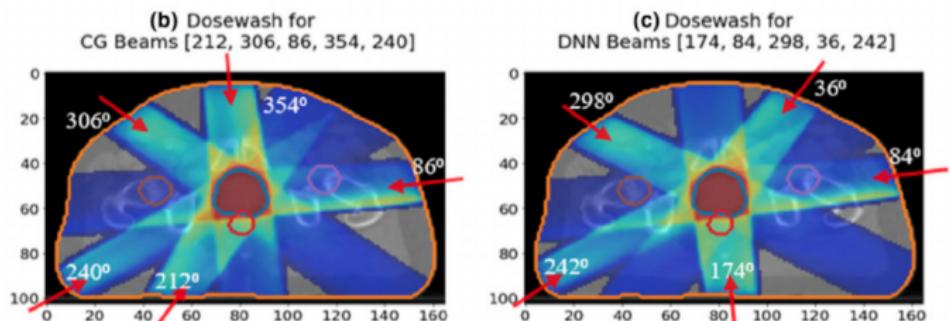
iDG

Robustness issues

Approach

iDG Results

Future Work



Dose-Volume Histogram of CG vs DNN architectures

Dose Volume Histograms

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation
Approach

Column Generation

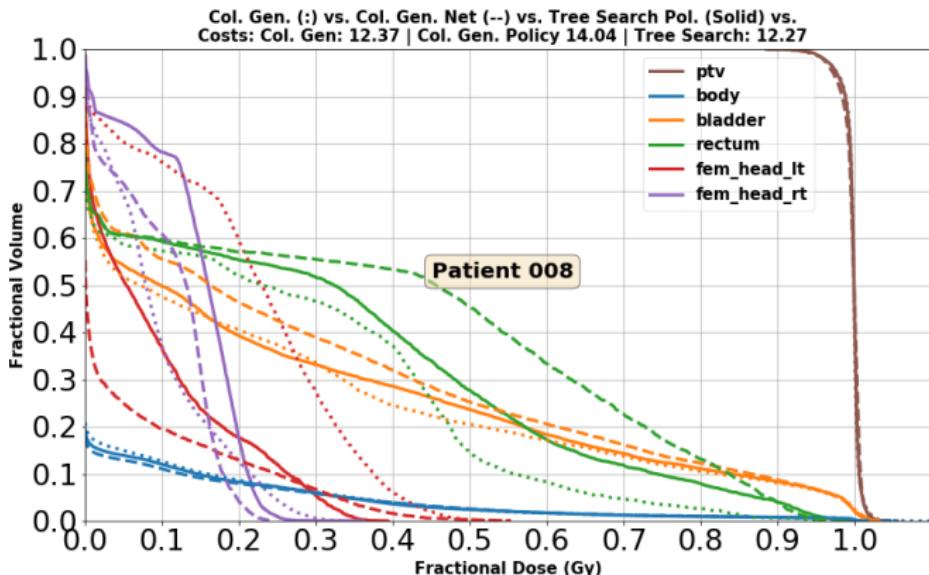
iDG

Robustness issues

Approach

iDG Results

Future Work



Conclusions

- Finding the good beam angle candidates is orders of magnitude faster than the current approaches
 - Based on a neural network generative model of an MDP
 - Sparse lookahead search builds tree with nodes labeled by state-action pairs in an alternating manner (2-3 minutes).
 - Tree built stagewise from root to nodes has fixed depth; sample rewards stored on edges connecting state-action with state nodes
- Beam angles prediction takes between 2-3 minutes with MCTS vs 1 minute with Column Generation Pretraining.

Part III: Robustness Margins and Robust Deep Policies

Automating Treatment Planning in Radiation Therapy

Lekan Ogunmolu

Introduction

IMRT

Neural Network Architecture

Head Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- Robustness Margins and Robust Deep Policies for Nonlinear Control

The robustness conundrum

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT
Neural Network
Architecture

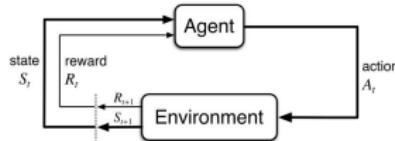
Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

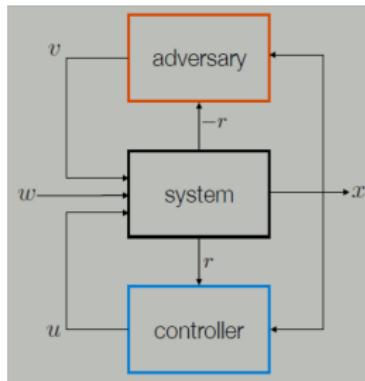
iDG
Robustness issues
Approach
iDG Results

Future Work

- How to know *a priori* a policy's robustness limits?



- How to inculcate robustness into multistage decision policies?



Problem Setup

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

- To quantify the brittleness, we optimize the stage cost

$$\max_{\mathbf{v}_t \sim \psi \in \Psi} \left[\sum_{t=0}^T \underbrace{c(\mathbf{x}_t, \mathbf{u}_t)}_{\text{nominal}} - \gamma \underbrace{g(\mathbf{v}_t)}_{\text{adversarial}} \right]$$

- To mitigate lack of robustness, we optimize the *cost-to-go*

$$\mathcal{J}_t(\mathbf{x}_t, \pi, \psi) = \min_{\mathbf{u}_t \sim \pi} \max_{\mathbf{v}_t \sim \psi} \left(\sum_{t=0}^{T-1} \ell_t(\mathbf{x}_t, \mathbf{u}_t, \mathbf{v}_t) + L_T(\mathbf{x}_T) \right),$$

- and seek a saddle point equilibrium policy that satisfies

$$\mathcal{J}_t(\mathbf{x}_t, \pi^*, \psi) \leq \mathcal{J}_t(\mathbf{x}_t, \pi^*, \psi^*) \leq \mathcal{J}_t(\mathbf{x}_t, \pi, \psi^*),$$

Results: Brittleness Quantification

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

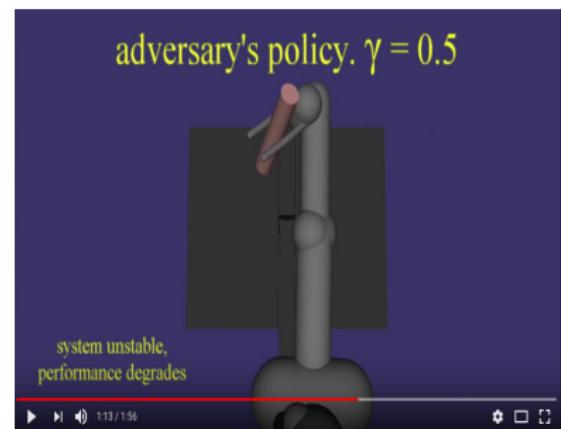
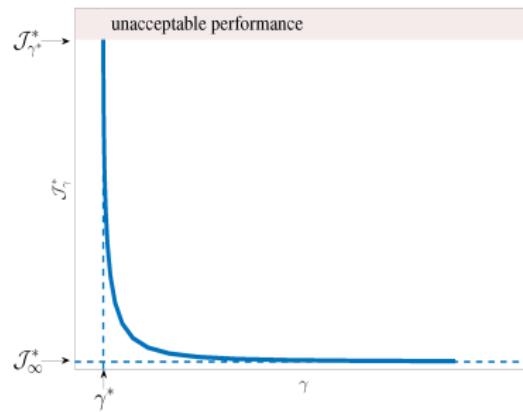
iDG

Robustness issues

Approach

iDG Results

Future Work



Results: Iterative Dynamic Game

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

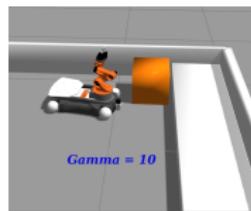
Robustness issues

Approach

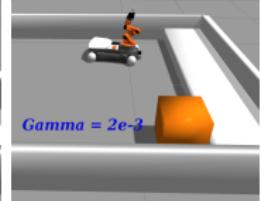
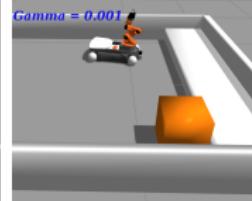
iDG Results

Future Work

y_1^*



y_2^*



End pose of the KUKA platform with our iDG formulation given different goal states and γ -values

Future Work: MRI/RT Immobilization

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT
Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

- Explore multiple parallel robot mechanisms for head motion correction.
- Adopt iterative dynamic game approach [Ogunmolu et al. (2018)] for solving robust controller for head stabilization.
- Build on Freeman and Kokotovic's point-wise min-norm robust control lyapunov function to realize a meaningful value function in deep policies [Freeman and Kokotovic (1996)].

Conclusions

- Designed a non-invasive soft robot for head motion compensation in IMRT/emerging MRI-LINACs ✓
- Photons-transparent; Adaptable under MRI coils for newer MRI-LINACs ✓
- Fast inference of beam orientations in treatment planning:
Approx 60 secs beams prediction time✓
- Adapted H_{∞} control methods for quantifying the brittleness of deep policies✓
- Devised a min-max-trained deep saddle policy for mitigating model mismatch, transfer errors, and policy sensitivity e.t.c. ✓

Acknowledgments

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction
IMRT
Neural Network
Architecture

Head
Stabilization
MRI-LINACs

BOO
MCTS
BOO Motivation
Approach
Column Generation

iDG
Robustness issues
Approach
iDG Results

Future Work

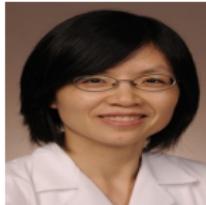
Steve Jiang, UTSW



Nick Gans, UTARI



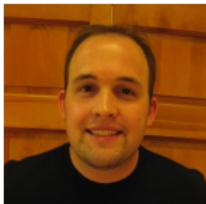
Xuejun Gu, UTSW



Dan Nguyen, UTSW



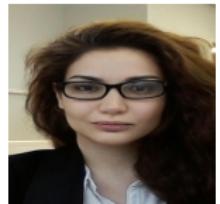
Rod Wiersma, Penn



Tyler Summers, UTD



Yonas Tadesse, UTD



Azar S.B., UTSW

Publications

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

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Publications

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

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Publications

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

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End of Slides

Automating
Treatment
Planning in
Radiation
Therapy

Lekan
Ogunmolu

Introduction

IMRT

Neural Network
Architecture

Head
Stabilization

MRI-LINACs

BOO

MCTS

BOO Motivation

Approach

Column Generation

iDG

Robustness issues

Approach

iDG Results

Future Work

Thank you!