

Accepted Manuscript

Real-time Localization of Articulated Surgical Instruments in Retinal Microsurgery

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PII: S1361-8415(16)30032-9
DOI: [10.1016/j.media.2016.05.003](https://doi.org/10.1016/j.media.2016.05.003)
Reference: MEDIMA 1109

To appear in: *Medical Image Analysis*

Received date: 14 January 2016
Revised date: 3 May 2016
Accepted date: 3 May 2016

Please cite this article as: Nicola Rieke, David Joseph Tan, Chiara Amat di San Filippo, Federico Tombari, Mohamed Alsheakhali, Vasileios Belagiannis, Abouzar Eslami, Nassir Navab, Real-time Localization of Articulated Surgical Instruments in Retinal Microsurgery, *Medical Image Analysis* (2016), doi: [10.1016/j.media.2016.05.003](https://doi.org/10.1016/j.media.2016.05.003)

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Highlights

- A method for instrument pose estimation in in-vivo RM sequences is proposed.
- The main idea is the modeling of the surgical instrument as an articulated object.
- By separating tracking and pose estimation, the method yields all joints in real-time.
- The algorithm can generalize for changes in illumination, background and tool shape.
- Evaluations on a public dataset imply that the method outperforms state-of-the-art.

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