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Intrafractional tracking accuracy in infrared marker-based hybrid dynamic tumour-tracking irradiation with a gimballed linac.

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Intrafractional accuracy of IR Tracking

1 **Intrafractional tracking accuracy in infrared marker-based hybrid**
2 **dynamic tumour-tracking irradiation with a gimballed linac**

3

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ABSTRACT

Purpose: To verify the intrafractional tracking accuracy in infrared (IR) marker-based hybrid dynamic tumour tracking irradiation (“IR Tracking”) with the Vero4DRT.

Materials and Methods: The gimballed x-ray head tracks a moving target by predicting its future position from displacements of IR markers in real-time. Ten lung cancer patients who underwent IR Tracking were enrolled. The 95th percentiles of intrafractional mechanical (iE_M^{95}), prediction (iE_P^{95}), and overall targeting errors (iE_T^{95}) were calculated from orthogonal fluoroscopy images acquired during tracking irradiation and from the synchronously acquired log files.

Results: Averaged intrafractional errors were (left-right, cranio-caudal [CC], anterior-posterior [AP]) = (0.1 mm, 0.4 mm, 0.1 mm) for iE_M^{95} , (1.2 mm, 2.7 mm, 2.1 mm) for iE_P^{95} , and (1.3 mm, 2.4 mm, 1.4 mm) for iE_T^{95} . By correcting systematic prediction errors in the previous field, the iE_P^{95} was reduced significantly, by an average of 0.4 mm in the CC ($p < 0.05$) and by 0.3 mm in the AP ($p < 0.01$) directions.

Conclusions: Prediction errors were the primary cause of overall targeting errors, whereas mechanical errors were negligible. Furthermore, improvement of the prediction accuracy could be achieved by correcting systematic prediction errors in the previous field.

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INTRODUCTION

54 Respiratory motion is one of the factors causing uncertainties during beam delivery,
55 particularly for thoracic and abdominal tumours [1, 2]. In hypofractionated stereotactic
56 body radiotherapy for lung cancer patients, addition of a large margin to compensate for
57 respiratory motion increases the probability of complications [3]. Several techniques,
58 including forced shallow-breathing, breath-hold, respiratory gating, and dynamic tumour
59 tracking (DTT), have been proposed to reduce the uncertainties caused by respiratory
60 motion [1, 2]. Of these methods, recent interest has focused on the DTT technique, which
61 can reposition the radiation beam dynamically in accordance with the target position. DTT
62 can minimise the internal uncertainties without a burden on the respiration of patients or
63 prolongation of treatment time.

64 We have developed an innovative four-dimensional (4D) image-guided
65 radiotherapy system, the Vero4DRT (MHI-TM2000; Mitsubishi Heavy Industries, Ltd.,
66 Japan, and BrainLAB, Feldkirchen, Germany) [4-10], and used its hybrid DTT irradiation
67 function [infrared (IR)-marker-based hybrid DTT irradiation (“IR Tracking”)] clinically in
68 lung cancer patients since September 2011 [10]. In IR Tracking, the position of the target,
69 indicated by implanted fiducial markers, is calculated from external surrogate signals
70 through a pre-built prediction model (“4D model”), and the MV x-ray beam is delivered
71 with real-time monitoring [7, 8, 10-12]. Depuydt et al. showed that the performance of
72 Vero4DRT’s DTT function was comparable with other clinical DTT systems in phantom
73 and patient simulation studies [11, 12]. Our group also previously revealed that the
74 accuracy of the 4D model must be verified before treatment, and margins were required to

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compensate for the prediction error in a phantom study [7]; it was concluded that the accuracy of the 4D model was affected by the baseline drift of respiratory motion [8]. Here, we verified the intrafractional tracking accuracy of IR Tracking for lung cancer patients using intrafractional monitoring images and the corresponding log files.

MATERIALS AND METHODS

The Vero4DRT hybrid dynamic tumour tracking irradiation system

Supplementary Figure 1 (Electronic Appendix) shows a schematic diagram of the Vero4DRT system. The Vero4DRT has several unique components that facilitate DTT irradiation: (1) a compact C-band 6-MV x-ray head with a gimbal mechanism, mounted on an O-ring gantry. The gimballed x-ray head can swing itself in both the pan and tilt directions, (2) gantry-mounted orthogonal kV x-ray imaging subsystems, consisting of two sets of x-ray tubes and flat-panel detectors, with a spatial resolution of 0.2 mm at the isocentre level, and (3) an extended version of the ExacTRAC system that enables real-time motion monitoring and management for the DTT function [7, 8, 11, 12] with an IR camera mounted on the ceiling of the treatment room.

Supplementary Figure 2 shows a schematic diagram of the IR Tracking procedure. After patient positioning, a 4D model is created using synchronously monitored internal target motion and an external surrogate signal. The detected target position (P_d) is defined as the tumour centre-of-mass calculated from the positions of the implanted fiducial markers on the x-ray images. The relative shift amount between the tumour centre-of-mass and centroid of the markers' polyhedron was determined at the end-exhalation phase in the

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planning computed tomography. The predicted target position (P_p) is calculated from the 4D model, expressed by a quadratic equation involving two variables, the position and velocity of the IR markers. The positions of the IR markers are predicted linearly from the past motion to compensate for the DTT system delay [11]. Details of the prediction model are described in the Supplementary Materials section. In this 4D-modelling phase, the peak-to-peak amplitude of the detected target motion (A) and the mean (μ) and standard deviation (SD) of the absolute 4D-modelling error (E_{4DM}), defined as the absolute difference between the P_p and P_d , are calculated along each axis automatically. During beam delivery, the future 3D target position is calculated from the displacements of the IR markers using the 4D model, and then the corresponding tracking angle is transferred continuously to the gimballed x-ray head. Additionally, circles with a user-defined radius around the predicted positions of the fiducial markers (tolerance circles) are displayed on the monitoring images as a benchmark in re-modelling. When the fiducial markers are deviated systematically from the tolerance circles, re-modelling should be performed during each treatment session (Fig. 1).

Patient characteristics and treatment planning

Ten lung cancer patients who underwent IR Tracking in an Institutional Review Board-approved trial were included in the present study. Patient selection criteria were based on our stereotactic body radiation therapy protocol and written informed consent for the present study was obtained from each patient [3, 10]. Three or more 1.5-mm-diameter gold markers (Olympus Co., Tokyo, Japan) were implanted around the lung tumour

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transbronchially 1–2 weeks before treatment planning. Table 1 shows the characteristics of the patients and treatment planning. We performed a dry-run treatment session prior to treatment planning to assess the characteristics of respirations and to identify patient-specific planning target volume (PTV) margins [7, 9]. The median of A was 2.8 mm in the left-right (LR), 15.8 mm in the cranio-caudal (CC), and 4.3 mm in the anterior-posterior (AP) directions. The median of $\mu+2SD$ of the E_{4DM} during the dry-run treatment session ($E_{4DM}^{\mu+2SD}$) was 0.6 mm in the LR, 1.9 mm in the CC, and 0.7 mm in the AP directions. Patient-specific PTV margins of 5.0–9.0 mm were added to the tumour along each axis to compensate for intra- and interfractional uncertainties in IR Tracking [7, 9, 13]. Supplementary Figure 3 shows the definition of the patient-specific PTV margins. The intra- and interfractional uncertainties were classified into systematic and random components. The patient-specific PTV margins were then calculated for each axis using the formula in Supplementary Figure 3. Prescribed doses of 48 or 56 Gy were specified to isocentre in four fractions. Treatment plans included 6-8 non-coplanar fields, with a dose rate of 500 MU/min.

Data acquisition during beam delivery

During beam delivery, the target and fiducial markers were monitored using orthogonal kV x-ray imaging subsystems at 1 Hz. The predicted target positions and tracking angles of the gimballed x-ray head were recorded in log files at 60 and 200 Hz, respectively. In total, 9268 paired images (~30 paired images per field) and corresponding log files were acquired.

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142 ***Verification of intrafractional tracking accuracy***
143 Intrafractional tracking accuracy was verified by the P_d from the fluoroscopic images and
144 the corresponding P_p and the tracked target position, calculated from the synchronously
145 acquired log files. Supplementary Figure 4 shows the geometric point of the tracked target
146 position at the depth of the P_d ($P_{t,d}$). The tracked target position at the depth of the P_p ($P_{t,p}$),
147 was calculated similarly. Intrafractional mechanical (iE_M), prediction (iE_P), and overall
148 targeting errors (iE_T) were defined as the differences between $P_{t,p}$ and P_p , P_p and P_d , and $P_{t,d}$
149 and P_d , respectively. Details of the calculation process are described in the Supplementary
150 Materials section.

151 The 95th percentiles of the absolute iE_M (iE_M^{95}), iE_P (iE_P^{95}), and iE_T (iE_T^{95}) during
152 the treatment course were then calculated using the intrafractional monitoring images and
153 the corresponding log files. Pearson correlation coefficients were calculated to assess the
154 relationship between $E_{4DM}^{\mu+2SD}$ during the dry-run treatment session and iE_P^{95} or iE_T^{95}
155 during the treatment course. To further improve the prediction accuracy, the corrected iE_P^{95}
156 was recalculated retrospectively by subtracting the systematic (*i.e.* signed overall mean) iE_P
157 in the previous field excluding the first field after the 4D modelling. A paired *t*-test with a
158 0.05 significance level was performed for statistical analysis.

RESULTS

161 Table 2 summarises iE_M^{95} , iE_P^{95} , iE_T^{95} , and corrected iE_P^{95} for 10 lung cancer patients.

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162 Averaged intrafractional tracking errors were (LR, CC, AP) = (0.1 mm, 0.4 mm, 0.1 mm)
163 for iE_M^{95} , (1.2 mm, 2.7 mm, 2.1 mm) for iE_P^{95} , and (1.3 mm, 2.4 mm, 1.4 mm) for iE_T^{95} .
164 Additionally, a strong positive correlation was found between $E_{4DM}^{\mu+2SD}$ and iE_P^{95} (LR, CC,
165 AP) = (0.73 [$p = 0.017$], 0.82 [$p = 0.003$], 0.96 [$p = 0.000$]) or iE_T^{95} (LR, CC, AP) = (0.69
166 [$p = 0.028$], 0.77 [$p = 0.010$], 0.90 [$p = 0.001$]). As shown in Table 2, iE_P^{95} was the
167 primary cause of iE_T^{95} , while iE_M^{95} was negligible. The iE_T^{95} was fully covered by the
168 PTV margin, including the geometric variations between the tumour and fiducial markers.
169 Figure 2 (a) shows representative probability histograms in the positional error in the CC
170 direction for the first patient who underwent IR Tracking (Patient No. 1). iE_T^{95} was
171 2.3 mm for this patient.

172 A maximum iE_T^{95} of 4.1 mm was observed for Patient No. 7 in the CC direction.
173 This patient showed the largest difference between $E_{4DM}^{\mu+2SD}$ and iE_P^{95} [LR, CC, and AP =
174 1.6, 1.5, and 1.6 mm, respectively] due to a baseline drift during beam delivery. Meanwhile,
175 the averaged differences for the other patients were 0.3, 0.6, and 0.7 mm for the LR, CC,
176 and AP directions, respectively. By correcting the systematic prediction errors in the
177 previous field, however, iE_P^{95} decreased, from 4.1 to 2.7 mm, for this patient in the CC
178 direction [Fig. 2 (b)]. The maximum reductions in iE_P^{95} were observed in this patient (LR,
179 CC, AP) = (1.4 mm, 1.4 mm, 0.9 mm). For the entire population, the corrected iE_P^{95} was
180 improved significantly by an average of 0.4 mm in the CC ($p < 0.05$) and by 0.3 mm in the
181 AP ($p < 0.01$) directions.

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DISCUSSION

184 The Vero4DRT tracks a moving target in real-time using the orthogonal gimballed x-ray
185 head. In the present study, we established a verification methodology for the intrafractional
186 mechanical, prediction, and overall targeting accuracy in each axis during the treatment
187 course. The 3D coordinates of the intrafractional tracked target position were calculated
188 based on the MV x-ray beam orientation using intrafractional monitoring images and the
189 corresponding log files.

190 We verified the intrafractional tracking accuracy for 10 lung cancer patients who
191 underwent IR Tracking with real-time monitoring. Vero4DRT users can monitor the moving
192 target, fiducial markers, and tolerance circles with its predicted position using orthogonal
193 kV x-ray imaging subsystems during beam delivery. At our institution, the radius of the
194 tolerance circles is set to 3 mm, and the 4D model is re-modelled when the monitored
195 fiducial markers' positions are displaced systematically from the tolerance circles due to
196 baseline drift (Fig. 1). By re-modelling the 4D model, while an iE_T^{95} of less than 3 mm
197 was achieved for nine patients (90%), one patient (Patient No. 7) showed a large iE_T^{95} of
198 greater than 3 mm. The 4D model was updated once during the treatment session for
199 Patient No. 7. However, this patient required additional re-modelling. In IR Tracking, the
200 predominant cause of overall targeting errors was prediction errors. The position and
201 velocity of IR markers involved in the 4D model were predicted linearly from past IR
202 marker motion [8]. Thus, prediction uncertainty of the peak position sometimes
203 overestimated the predicted position of the IR marker and the 4D model enforced a large

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204 amplitude of respiration motion (Supplementary Figure 5). In this case, the mechanical
205 response delay of the gimballed x-ray head reduced the impact of the prediction error on
206 the overall targeting error. Thus, the overall targeting errors were sometimes smaller than
207 the prediction errors. Additionally, there were strong correlations between $E_{4DM}^{\mu+2SD}$ and
208 iE_p^{95} or iE_T^{95} , indicating that intrafractional prediction or overall targeting errors during
209 the treatment course could be estimated from 4D modelling errors during the dry-run
210 treatment session. The iE_T^{95} was fully covered by the PTV margin, including a geometric
211 variation between the tumour and fiducial markers of 2.5 mm (Tables 1 and 2). When
212 calculating the PTV margin in IR Tracking, the intra- and interfractional uncertainties
213 should be considered (Supplementary Figure 3). However, the present recipe of the
214 patient-specific PTV margin was tentative so as to perform IR Tracking safely. Therefore,
215 further investigations will be needed to determine the PTV margin size appropriate for IR
216 Tracking [9].

217 The CyberKnife Robotic Radiosurgery System with the integrated Synchrony
218 Respiratory Tracking System (Accuray, Sunnyvale, CA) substantially reduces the
219 geometric error caused by respiratory motion [14, 15]. In the present study, $E_{4DM}^{\mu+2SD}$ was
220 comparable with results of the Synchrony system. However, the correlation between the
221 internal target positions and external surrogates can change in the presence of baseline drift,
222 reducing the accuracy of the prediction model [8, 16]. The Synchrony system periodically
223 updates the prediction model using the intrafractional monitoring images. Updating the 4D
224 model in real-time may also improve the prediction accuracy because the internal/external

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correlation change or baseline drift in respiration will be corrected. Meanwhile, this is difficult regarding image processing time and minimum interval of the x-ray acquisition during beam delivery. The 4D model in IR Tracking includes the parameters of position and velocity of the IR markers. To update the 4D model, these parameters must be changed. Thus, a shorter monitoring interval would be necessary. In clinical practice, we re-modelled the 4D model at least once during treatment to minimise intrafractional uncertainties due to internal/external correlation change or baseline drift in respiration. However, re-modelling required additional exposures that were 8.3-16.7 times higher than intrafractional monitoring [4, 12]. Also, x-ray image-based DTT, another DTT approach with Vero4DRT [6], would not be an alternative strategy in terms of the difficulty of real-time detection and excessive imaging doses. In the current study, the overall mean errors of iE_P were calculated from around 30 paired images retrieved in the previous field using the monitoring function for the intrafractional tracking accuracy verification. Because the systematic prediction errors resulting from the baseline drift of respiration were reduced by subtracting the overall mean errors of iE_P in the previous field, iE_P^{95} decreased significantly in the CC and AP directions using the monitoring images during beam delivery. In the current study, we used all monitoring images to calculate the systematic prediction errors because iE_P varied according to the respiratory phase. However, a triggered x-ray acquisition based on the respiratory phase would also reduce iE_P^{95} using a small number of monitoring images because the systematic prediction errors could be corrected by the averaged iE_P at the end-expiratory and end-inspiratory phases.

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CONCLUSIONS

We demonstrated that IR Tracking reduced the impact of respiratory motion substantially. The prediction error was the primary cause of the overall targeting error, while the mechanical error was negligible. The PTV margin fully covered the intrafractional overall targeting errors. The 4D modelling errors during a dry-run treatment session were a good indicator of the prediction and overall targeting errors during the treatment course. Additionally, further improvement in prediction accuracy was achieved by correcting the systematic prediction error in the previous field.

CONFLICTS OF INTEREST STATEMENT

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FIGURE LEGENDS

Figure 1. Screen shot of the Vero4DRT during infrared (IR)-marker-based DTT irradiation (“IR Tracking”). Monitored fiducial markers’ positions were located outside of the “Tolerance circle” displayed around the predicted fiducial markers’ positions due to the baseline drift of respiration.

Figure 2. Probability histograms of positional errors in the cranio-caudal (CC) direction (a) for the first patient who underwent IR Tracking (Patient No. 1) and (b) for the most improved patient with intrafractional prediction error (iE_P) correction (Patient No. 7). The Vero4DRT reduced the motion blurring effect caused by respiration.

TABLES

Table 1. Characteristics of the patients and treatment planning.

Patient no.	Age (y.o.)	Sex	Tumour stage	Tumour side	Tumour location	A [mm]			$E_{4DM}^{\mu+2SD}$ [mm]			GTV [cc]	PTV margin [mm]			PTV [cc]
						LR	CC	AP	LR	CC	AP		LR	CC	AP	
1	85	F	Metastasis	Rt	S6	2.2	14.8	2.2	0.2	1.4	0.6	38.7	5.0	7.0	5.0	87.0
2	82	M	T1a	Rt	S9	4.6	19.8	4.4	1.6	3.3	0.5	11.0	5.0	8.0	5.0	34.6
3	86	F	T1b	Rt	S9	2.2	26.0	5.3	0.2	1.6	0.8	12.4	5.0	8.0	5.0	38.0
4	84	M	T1b	Rt	S6	0.9	11.9	3.1	0.3	1.3	0.7	17.8	5.0	7.0	5.0	50.1
5	71	M	T1b	Rt	S5	7.4	3.4	5.1	1.3	1.0	0.7	12.5	5.0	5.0	5.0	33.6
6	87	M	T1b	Lt	S8	2.9	29.6	15.5	0.6	2.2	3.9	20.6	5.0	8.0	8.0	64.1
7	61	M	T2a	Rt	S10	1.4	8.8	4.0	0.5	2.6	0.7	31.9	5.0	6.5	5.0	74.2
8	85	M	T1a	Lt	S9	5.8	30.6	8.7	2.1	3.4	2.9	8.9	5.0	9.0	6.0	33.4
9	68	M	Metastasis	Lt	S8	2.7	9.9	2.3	0.2	0.9	0.4	2.3	5.0	5.0	5.0	10.4
10	60	M	Metastasis	Rt	S9	3.1	16.7	4.1	0.9	2.2	1.6	13.3	5.0	7.0	5.0	38.9

Abbreviations: A=peak-to-peak amplitude of respiration, $E_{4DM}^{\mu+2SD}$ = mean plus two standard deviations of the absolute 4D-modelling error during a dry-run treatment session, GTV=gross tumour volume, PTV=planning target volume, LR=left-right, CC=cranio-caudal, AP=anterior-posterior, F=Female, M=Male, Rt=Right lobe, Lt=Left lobe, S= pulmonary segment.

Table 2. iE_M^{95} , iE_P^{95} , iE_T^{95} , and corrected iE_P^{95} .

Patient no.	iE_M^{95} [mm]			iE_P^{95} [mm]			iE_T^{95} [mm]			Corrected iE_P^{95} [mm]		
	LR	CC	AP	LR	CC	AP	LR	CC	AP	LR	CC	AP
1	0.1	0.3	0.1	0.6	2.7	1.3	0.9	2.3	1.0	0.6	1.9	1.2
2	0.3	0.7	0.2	1.4	3.4	0.8	1.3	3.0	0.7	1.3	3.1	0.6
3	0.1	0.4	0.1	0.7	2.5	1.5	0.8	2.2	1.0	0.7	2.7	1.3
4	0.1	0.4	0.1	0.8	2.0	1.5	0.8	1.7	1.0	0.8	1.7	1.4
5	0.1	0.1	0.1	1.8	1.5	1.6	1.1	1.5	1.2	1.5	1.5	1.6
6	0.1	0.3	0.1	1.0	2.5	5.0	1.9	2.3	2.9	0.9	1.8	4.3
7	0.2	0.8	0.2	2.1	4.1	2.3	1.4	4.1	1.6	0.7	2.7	1.4
8	0.2	0.4	0.1	2.1	3.2	3.4	2.2	2.8	1.6	2.5	3.2	3.2
9	0.1	0.3	0.1	0.5	1.6	1.4	0.8	1.4	0.9	0.4	1.3	1.1
10	0.1	0.3	0.1	1.1	3.0	2.0	1.3	2.9	1.6	1.0	2.7	1.8
Average	0.1	0.4	0.1	1.2	2.7	2.1	1.3	2.4	1.4	1.0	2.3	1.8

Abbreviations: iE_M^{95} =95th percentiles of the absolute intrafractional mechanical error, iE_P^{95} =95th percentiles of the absolute intrafractional prediction error, iE_T^{95} =95th percentiles of the absolute intrafractional overall targeting error, LR=left-right, CC=cranio-caudal, AP=anterior-posterior.

Figure 1

[Click here to download high resolution image](#)

Prediction model of the Vero4DRT

Before irradiation, a prediction model (“4D model”) was created. Infrared (IR) marker displacements and the implanted fiducial markers’ motions were monitored for 20-40 s using the IR camera of the ExacTRAC system every 16.7 ms and the orthogonal kV x-ray imaging subsystems every 80 or 160 ms, respectively. The frame rate of x-ray monitoring changed automatically depending on IR marker velocity.

After monitoring, two target positions are determined: the detected target position (P_d) and the predicted target position (P_p). The P_d is defined as the tumour centre-of-mass calculated from the positions of the implanted fiducial markers on the x-ray images. The relative shift amount between the tumour centre-of-mass and centroid of the markers’ polyhedron was determined at the end-exhalation phase in the planning computed tomography. The positions of the implanted fiducial markers were detected automatically based on the intensity ratios of the fiducial markers to their surroundings with an accuracy of 0.2 mm. The P_p is calculated from the predicted position and velocity of IR markers using the 4D model, expressed as follows:

$$P_p = \begin{pmatrix} x_p \\ y_p \\ z_p \end{pmatrix} = \frac{1}{n} \begin{pmatrix} \sum_{i=1}^n (a_{x,i}s_i^2 + b_{x,i}s_i + c_{x,i} + d_{x,i}v_i^2 + e_{x,i}v_i) \\ \sum_{i=1}^n (a_{y,i}s_i^2 + b_{y,i}s_i + c_{y,i} + d_{y,i}v_i^2 + e_{y,i}v_i) \\ \sum_{i=1}^n (a_{z,i}s_i^2 + b_{z,i}s_i + c_{z,i} + d_{z,i}v_i^2 + e_{z,i}v_i) \end{pmatrix} \quad (\text{equation1}),$$

where x_p , y_p , and z_p are the predicted target positions in the left-right, cranio-caudal, and anterior-posterior directions, n is the number of IR markers, and s and v are the predicted position and velocity of each IR marker in the anterior-posterior direction. The positions of

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20 the IR markers are predicted from the past motion to compensate for DTT system delay.
21 Parameters of the 4D model (a , b , c , d , and e) were optimised using a least-squares
22 algorithm so that residual errors between the P_p and P_d were minimised.

23 During beam delivery, the future 3D target position is predicted from the
24 displacements of the IR markers using the 4D model, and then the corresponding tracking
25 angle is transferred continuously to the gimballed x-ray head.

26

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27 ***Tracked target position calculated from the tracking angle of the gimballed x-ray head***

28 Intrafractional tracking accuracy was assessed by the detected target position (P_d) from the
29 fluoroscopic images and the corresponding predicted target position (P_p) and the tracked
30 target position, calculated from the synchronously acquired log files. The tracked target
31 position was derived from an intersection of a tracking orientation of the gimballed x-ray
32 head with a tracked tumour plane. The tracked tumour plane was defined as the
33 perpendicular plane to the gimbal angle of 0° for each port at the depth of the moving
34 tumour. The tracked target position, based on P_d ($P_{t,d}$), was calculated in the following three
35 steps:

36 (1) Conversion of P_d from room to gantry-ring coordinates:

37
$$\begin{pmatrix} u_d \\ v_d \\ w_d \end{pmatrix} = \begin{pmatrix} \cos G \cos R & -\cos G \sin R & -\sin G \\ -\sin R & -\cos R & 0 \\ \sin G \cos R & -\sin G \sin R & \cos G \end{pmatrix} \cdot \begin{pmatrix} x_d \\ y_d \\ z_d \end{pmatrix} \quad (\text{equation 2}),$$

38 where x_d , y_d , and z_d are the detected target positions along the LR, the CC, and the AP
39 directions in room coordinates, and G and R are the gantry and ring angle, and u_d , v_d , and
40 w_d (units: mm) are the detected target positions in gantry-ring coordinates corresponding to
41 x_d , y_d , and z_d .

42 (2) Calculation of $P_{t,d}$ at the depth of P_d in gantry-ring coordinates

43
$$\begin{pmatrix} u_{t,d} \\ v_{t,d} \\ w_{t,d} \end{pmatrix} = \begin{pmatrix} (960 - w_d) \tan \theta_p \\ (960 - w_d) \tan \theta_r \\ w_d \end{pmatrix} \quad (\text{equation 3}),$$

44 where $u_{t,d}$, $v_{t,d}$, and $w_{t,d}$ (units: mm) are the tracked target positions in gantry-ring

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coordinates at the depth of the detected target position ($w_{t,d}$). θ_p and θ_T are the pan and tilt angle of the gimballed x-ray head, and 960 mm is the distance from the rotation centre of the gimballed x-ray head to the isocentre.

(3) Conversion of $P_{t,d}$ from gantry-ring to room coordinates:

$$\begin{pmatrix} x_{t,d} \\ y_{t,d} \\ z_{t,d} \end{pmatrix} = \begin{pmatrix} \cos G \cos R & -\sin R & \sin G \cos R \\ -\cos G \sin R & -\cos R & -\sin G \sin R \\ -\sin G & 0 & \cos G \end{pmatrix} \begin{pmatrix} u_{t,d} \\ v_{t,d} \\ w_{t,d} \end{pmatrix} \text{ (equation 4),}$$

where $x_{t,d}$, $y_{t,d}$, and $z_{t,d}$ (units: mm) are the tracked target positions in room coordinates. The tracked target position, based on P_p ($P_{t,p}$), at the depth of the predicted target position (w_p) was calculated similarly.

Intrafractional mechanical (iE_M), prediction (iE_P), and overall targeting errors (iE_T) were defined as follows:

$$iE_M = \begin{pmatrix} x_{t,p} \\ y_{t,p} \\ z_{t,p} \end{pmatrix} - \begin{pmatrix} x_p \\ y_p \\ z_p \end{pmatrix} \text{ (equation 5),}$$

$$iE_P = \begin{pmatrix} x_p \\ y_p \\ z_p \end{pmatrix} - \begin{pmatrix} x_d \\ y_d \\ z_d \end{pmatrix} \text{ (equation 6),}$$

$$iE_T = \begin{pmatrix} x_{t,d} \\ y_{t,d} \\ z_{t,d} \end{pmatrix} - \begin{pmatrix} x_d \\ y_d \\ z_d \end{pmatrix} \text{ (equation 7),}$$

where $x_{t,p}$, $y_{t,p}$, and $z_{t,p}$ (units: mm) are the tracked target positions at the depth of the P_p used for the verification of the mechanical error of the gimballed x-ray head against the

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60 predicted target positions, and x_p , y_p , and z_p (units: mm) are the predicted target positions
61 used as the tracking commands to the gimballed x-ray head, and x_d , y_d , and z_d (units: mm)
62 are the detected target positions, and $x_{t,d}$, $y_{t,d}$, and $z_{t,d}$ (units: mm) are the tracked target
63 positions at the depth of the P_d used for the verification of the overall targeting error of the
64 gimballed x-ray head against the moving tumour.

65

66 **Supplementary Figure 1.** Schematic diagram of the Vero4DRT system.

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67

68 **Supplementary Figure 2.** Infrared (IR) marker-based hybrid dynamic tumour tracking

69 irradiation ("IR Tracking") procedure.

Patient-specific PTV margin

(1) Interfractional error

- Geometric uncertainty between Marker (M_n) and Target (T_n)
 - 2.5 mm

(2) Intrafractional error (Systematic)

- Baseline drift of respiration
 - 10% of peak-to-peak Amplitude

Amplitude

(3) Intrafractional error (Random)

- 4D modelling error
 - Mean + 2SD of absolute 4D modelling error

(4) Intrafractional error (Random)

- Mechanical error
 - 95th percentiles of mechanical error

$$PTV \text{ margin [mm]} = (1) + (2) + \sqrt{(3)^2 + (4)^2}$$

Minimum size of PTV margin was set to 5 mm

70

71 **Supplementary Figure 3.** Definition of the patient-specific planning target volume (PTV) margin.

72

73 **Supplementary Figure 4.** The geometric point of the tracked target position ($P_{t,d}$) based on the detected target position (P_d)

74 calculated from orthogonal fluoroscopic images and synchronously acquired log files.

75

76 **Supplementary Figure 5.** Screen shot of the Vero4DRT system during creation of the prediction model (“4D model”). The

77 right four groups of waves, from top to bottom, show variations in the infrared (IR) markers’ positions in the

78 anterior-posterior direction and the target positions in the lateral, craniocaudal, and anterior-posterior directions, respectively.

79 In the graphs of the target position, dark-coloured waves show the detected target position and light-coloured waves show the

80 predicted target position.