

2023 대한재활의학회 춘계학술대회

계측화된 동작분석의 발전 Instrumented Motion Analysis

나 동욱 (Rha, Dong-wook), MD, Ph.D

Professor

Dept. of rehabilitation medicine, YUMC

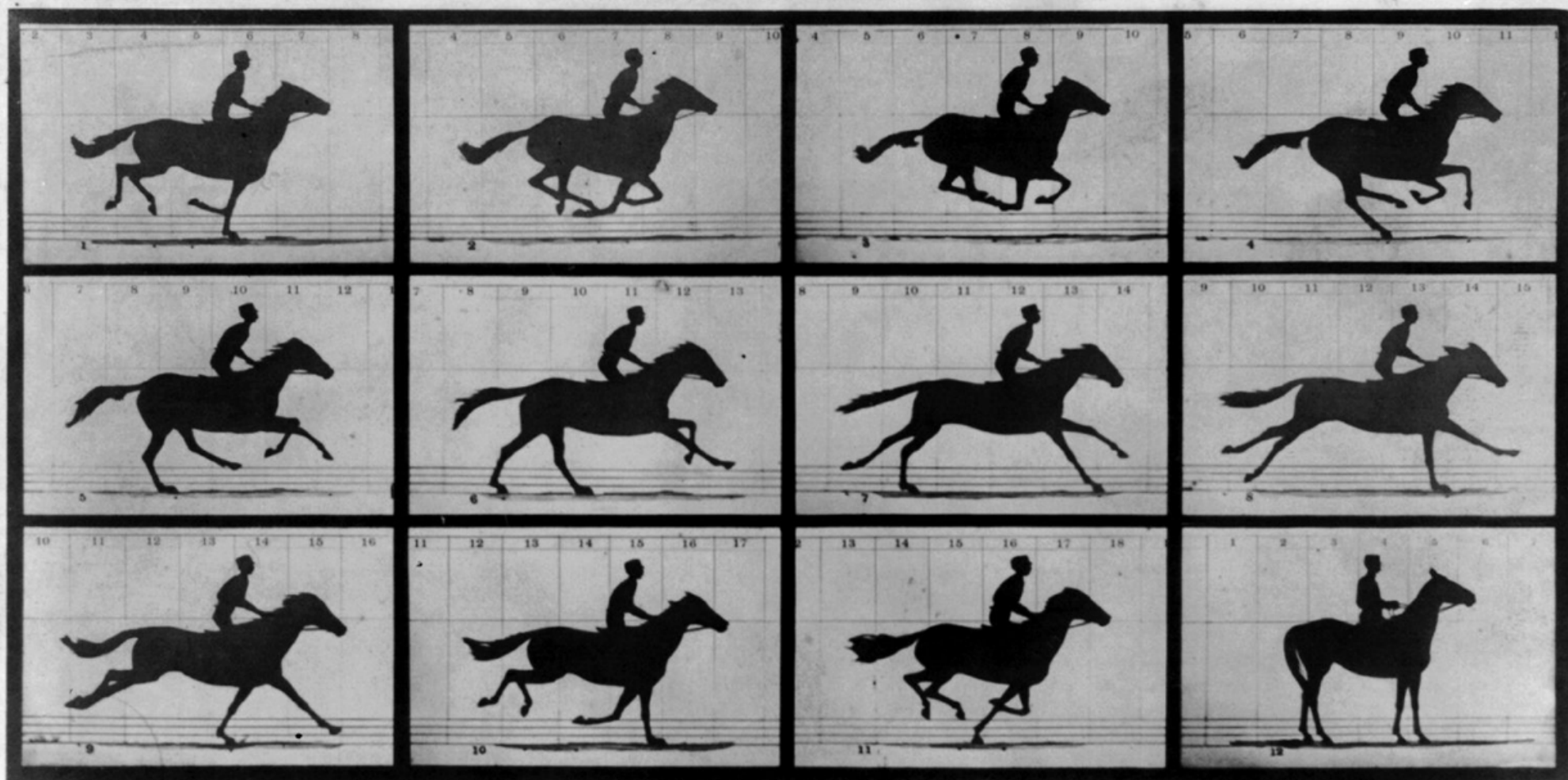
Severance rehabilitation hospital

BioMechanics and Robotic Rehabilitation(BMRR) Laboratory

<http://biomechanics.yonsei.ac.kr>

Eadweard Muybridge

- Photographer born at Apr 9, 1830
- Sallie Gardner at a Gallop (<http://www.youtube.com/watch?v=PqfCmQtrTcE>)
 - commissioned by Leland Stanford
 - whether a galloping horse ever lifts all 4 feet completely off the ground
 - Stanford's farm (Stockfarm) in Palo Alto on June 19, 1878
 - 24 cameras (27 inches apart): 58 km/h → 0.04 sec → 25fps



Copyright, 1878, by MUYBRIDGE.

MORSE'S Gallery, 417 Montgomery St., San Francisco.

THE HORSE IN MOTION.

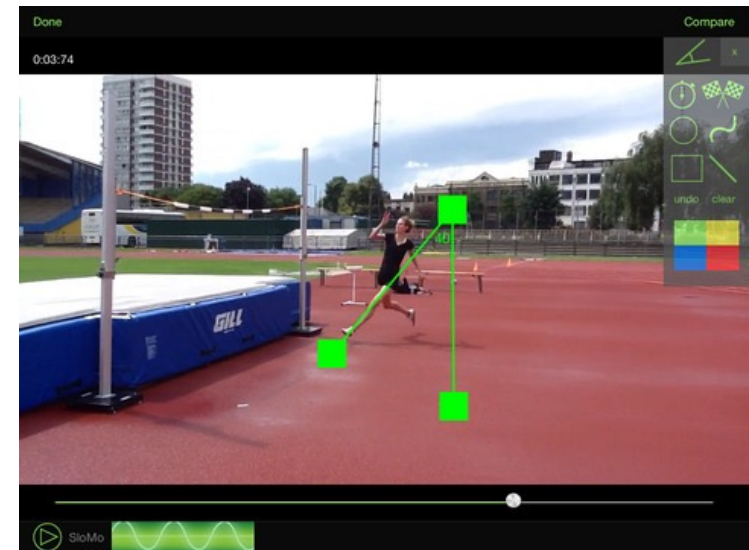
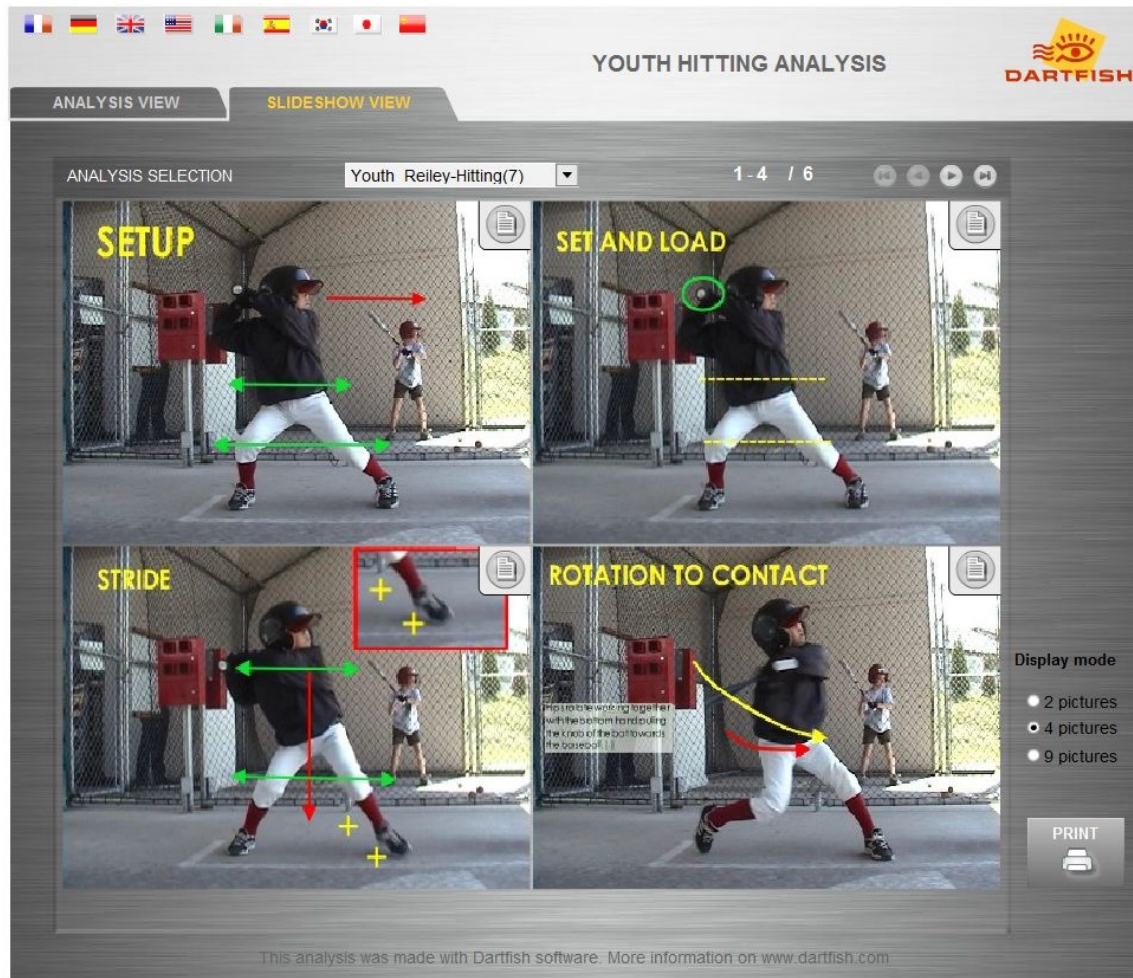
Illustrated by
MUYBRIDGE.

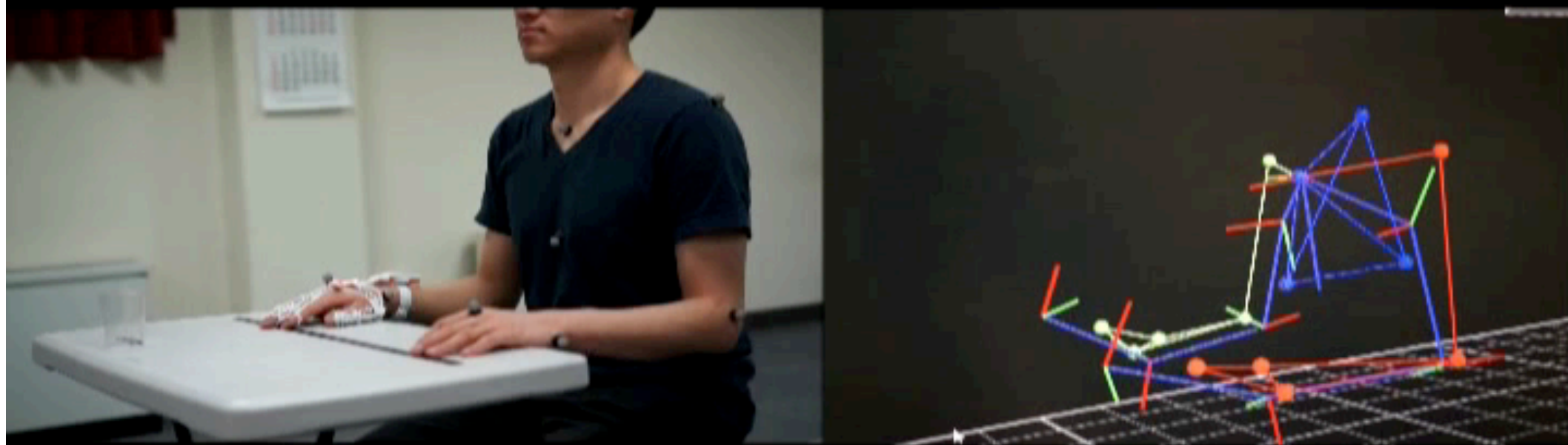
AUTOMATIC ELECTRO-PHOTOGRAPH.

"SALLIE GARDNER," owned by LELAND STANFORD; running at a 1.40 gait over the Palo Alto track, 19th June, 1878.

The negatives of these photographs were made at intervals of twenty-seven inches of distance, and about the twenty-fifth part of a second of time; they illustrate consecutive positions assumed in each twenty-seven inches of progress during a single stride of the mare. The vertical lines were twenty-seven inches apart; the horizontal lines represent elevations of four inches each. The exposure of each negative was less than the two-thousandth part of a second.

Motion capture - pictures

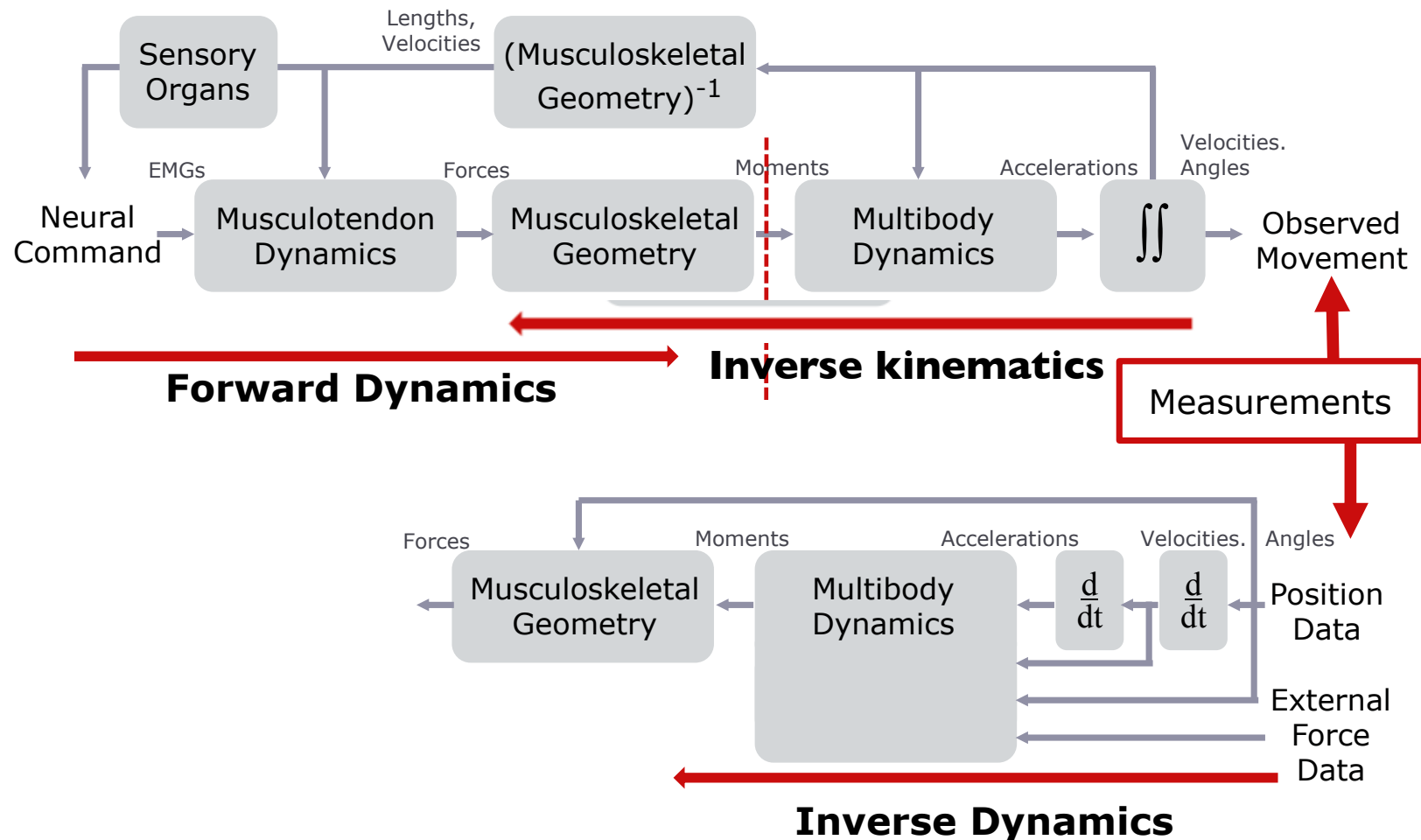




A wide-angle photograph of a laboratory room. The room has a grey carpeted floor with several blue square mats and white tape markings. The ceiling is white with a grid of square fluorescent light fixtures. In the background, there are computer workstations, a desk, and a window with red curtains. The text "Marker-based Motion Analysis" is overlaid in the center of the image.

Marker-based Motion Analysis

Motion Analysis ?



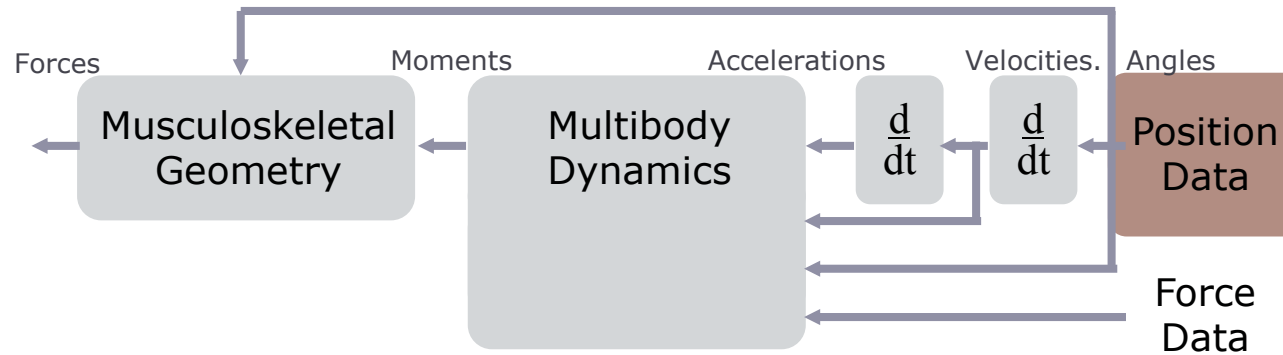
Computerized Motion Analysis

- Motion capture
- Kinematics : position, velocity and acceleration of body segments without consideration of causes
- Kinetics : relationship between motion and its causes, namely forces and torques
- EMG activity

Motion capture and Kinematics

- How can we determine the location of marker in space? -
 - How can we measure the joint angle? -

Motion capture system

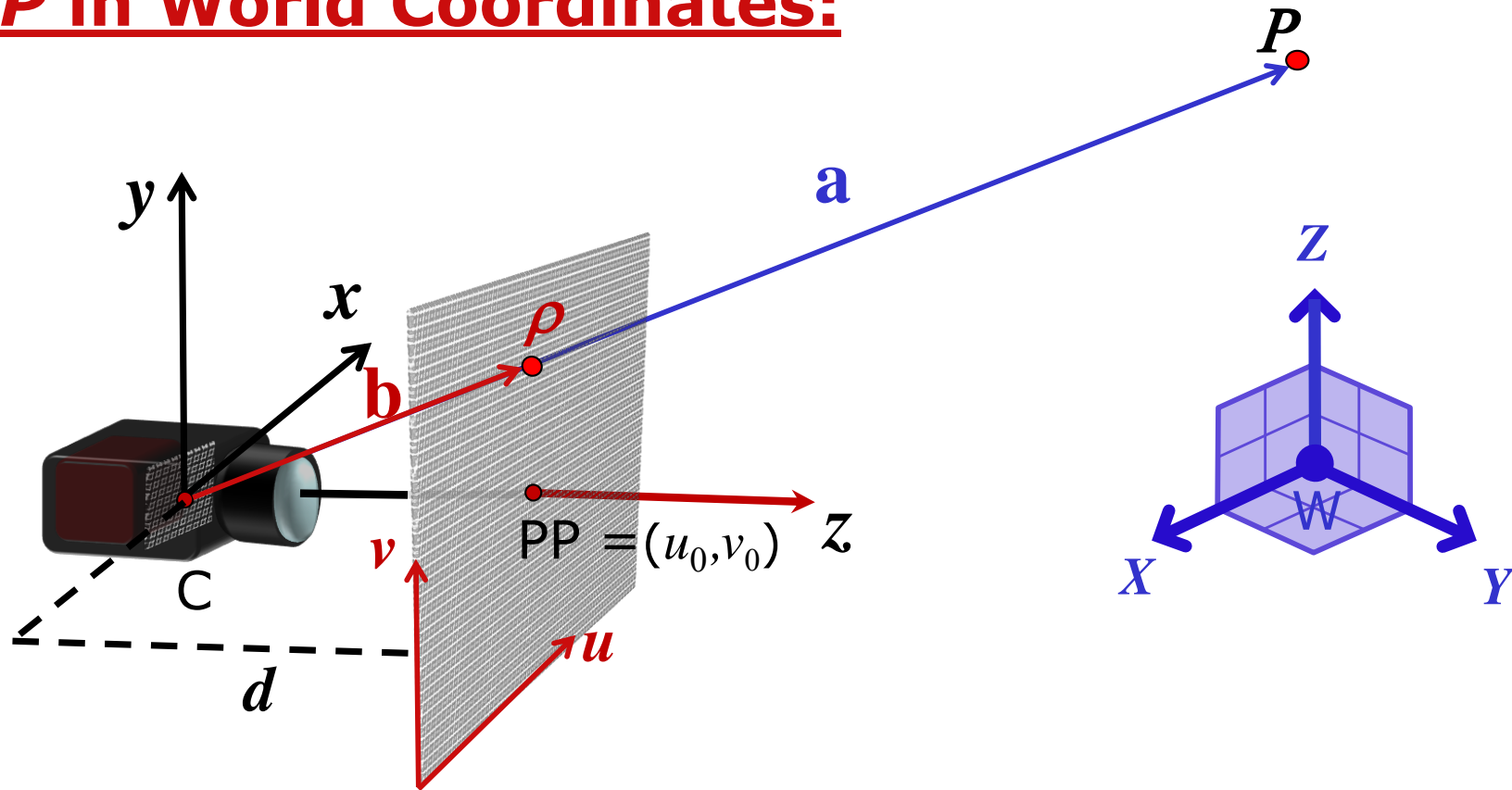


Optical System



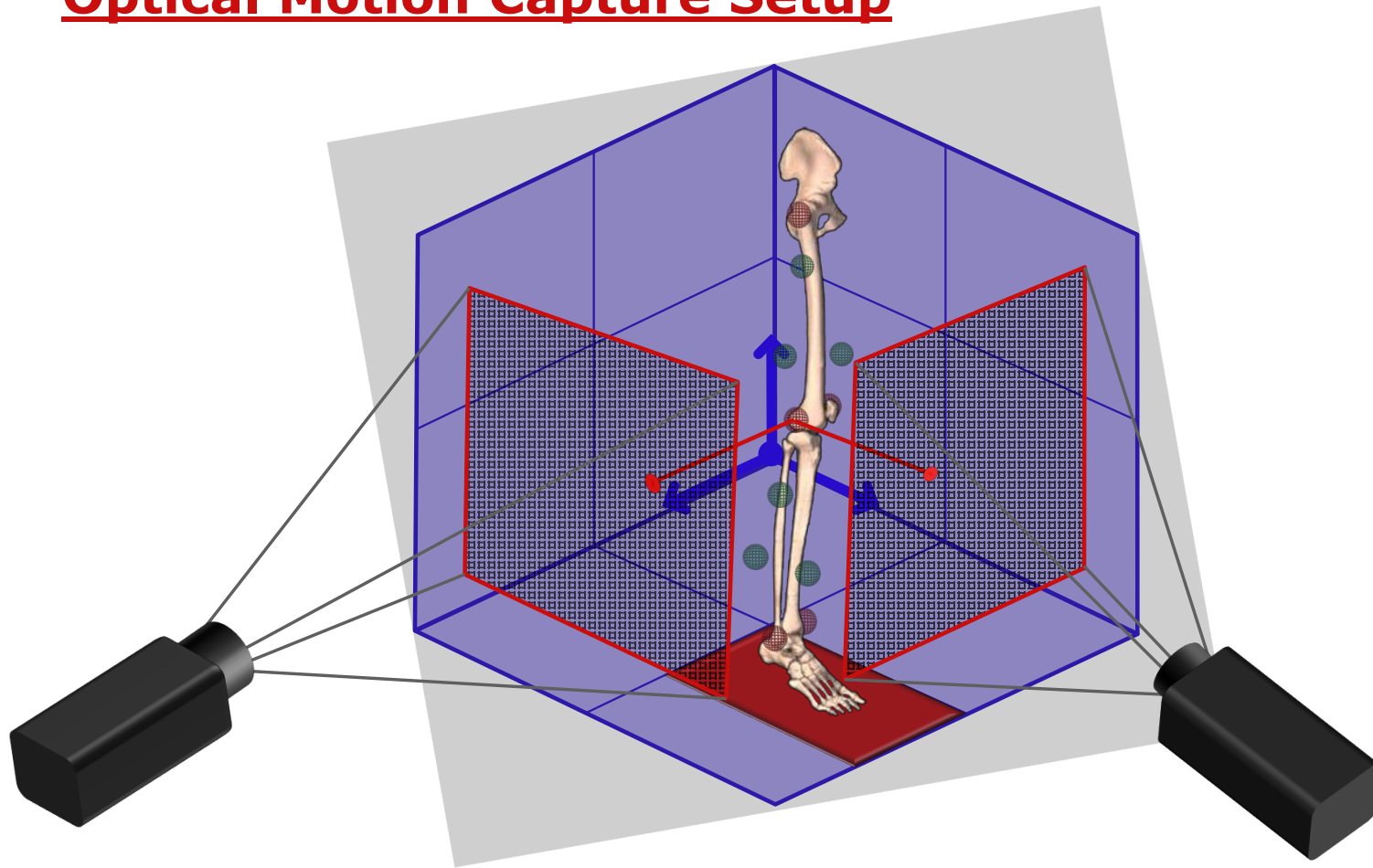
Motion capture technique (1)

P in World Coordinates:



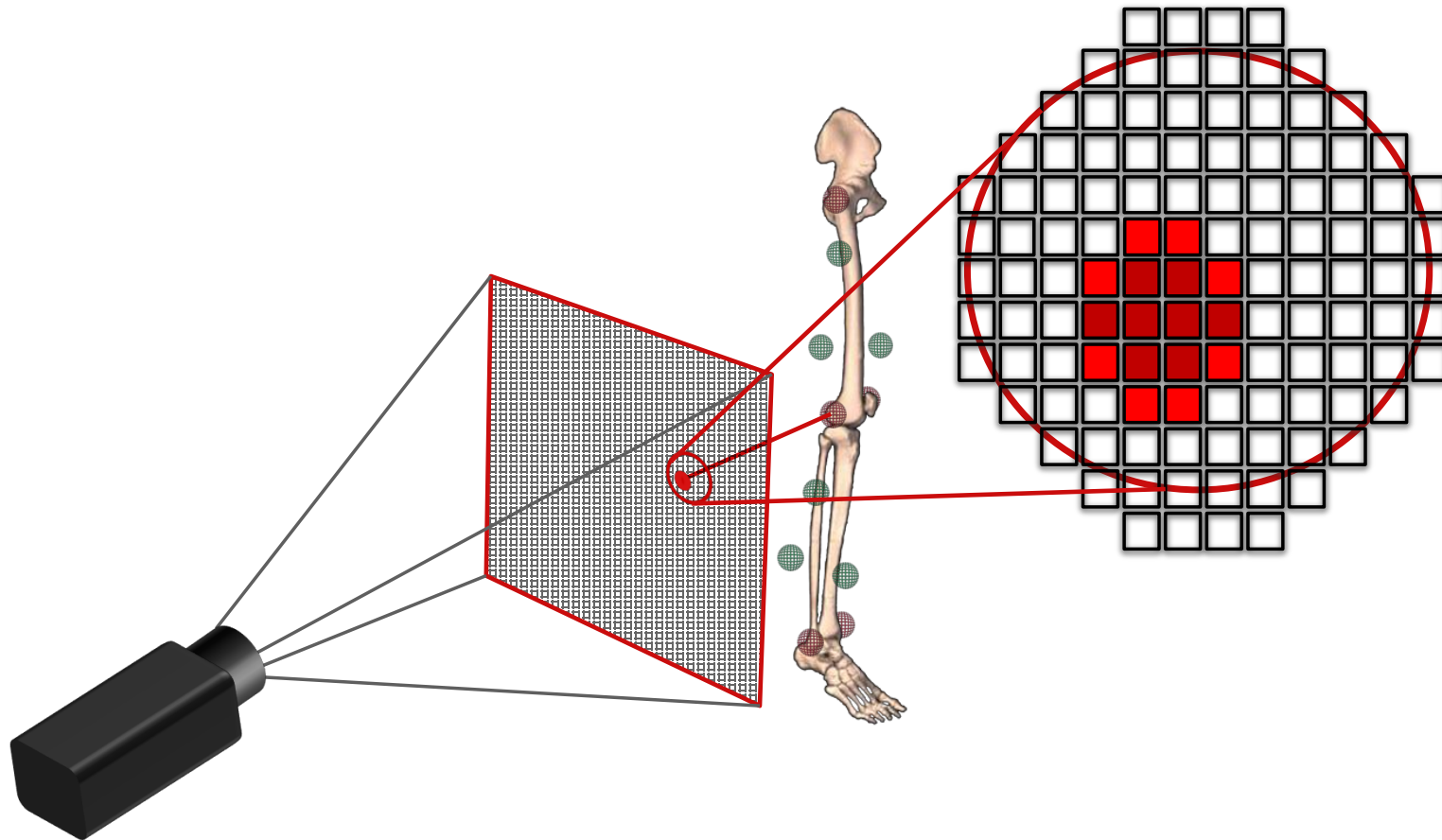
Motion capture technique (2)

Optical Motion Capture Setup



Motion capture technique (3)

Image Sensor Plane

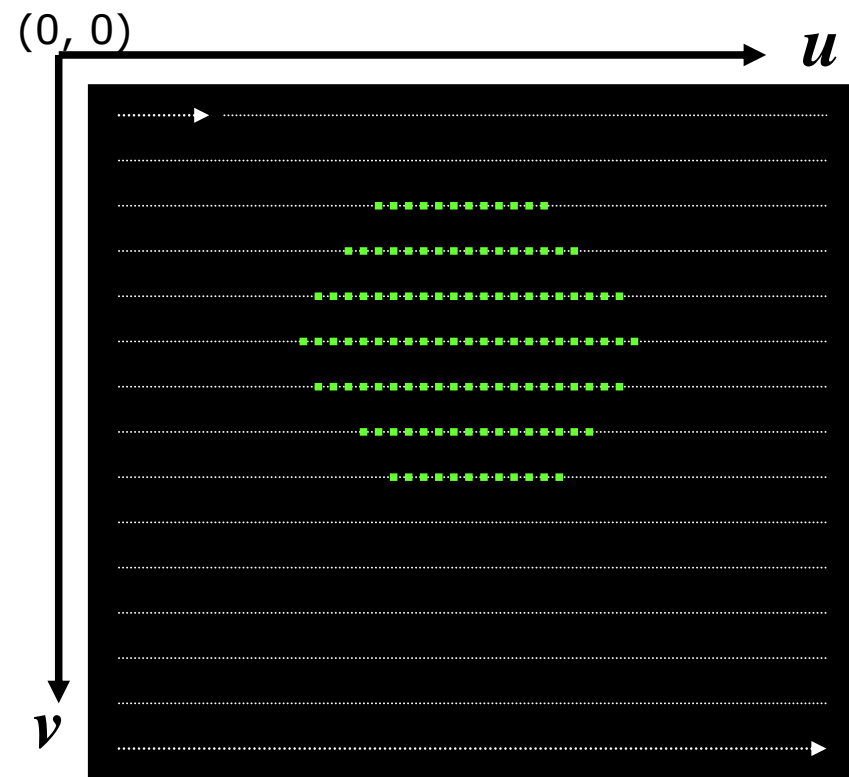


Capable of Detecting Many Markers at the Same Time

Motion capture technique (4)

Image Plane

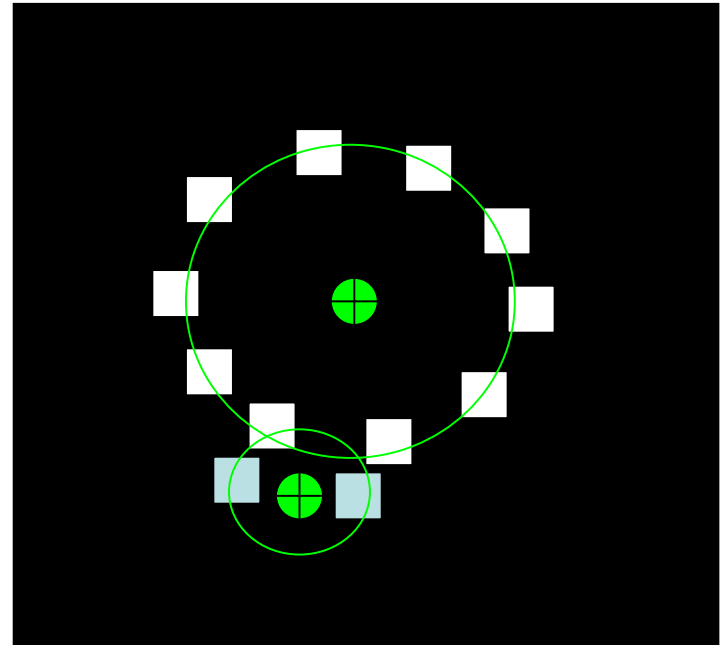
- Photosensitive detector array
- Resolution
 - **spatial** (pixels)
 - u horizontal
 - v vertical
 - **temporal**
 - scan rate



Motion capture technique (5)

Image Plane: Spatial Resolution

- More pixels are better!
- How many is reasonable?
 - Size of object
 - closeness of camera, related to field

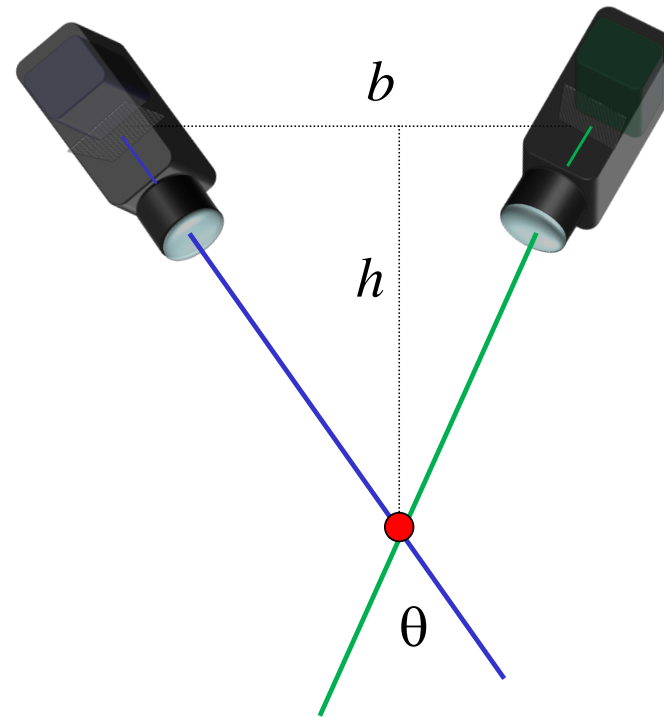


Spatial resolution

Motion capture technique (9)

Camera Placement

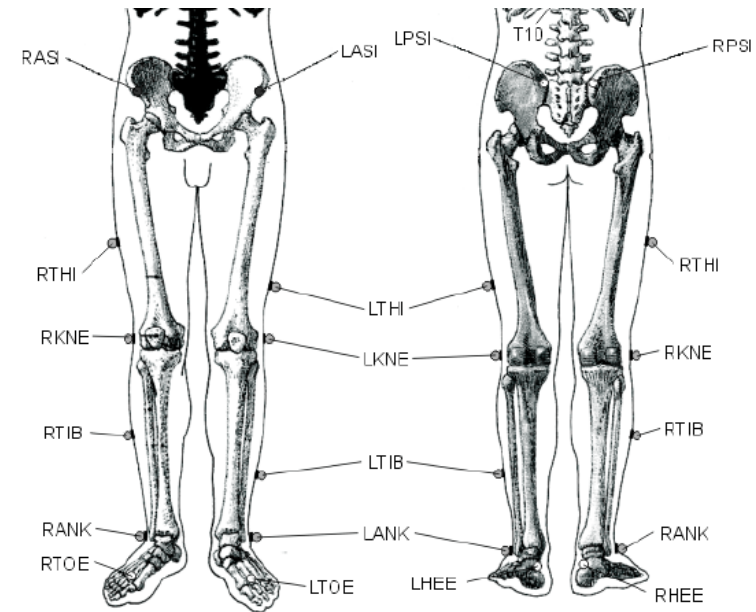
- If image planes are parallel, insufficient depth information
- Accuracy related to separation angle, θ
- Best when $\theta = 90^\circ$
 - do not fall below 60°
- base / length $\geq 0.3 - 0.4$



$$\theta > 60^\circ$$

$$b / h > 0.3$$

Marker to Skeletal Model



Plug in gait model (marker set) in Vicon system

Plug-in-gait model



Complex



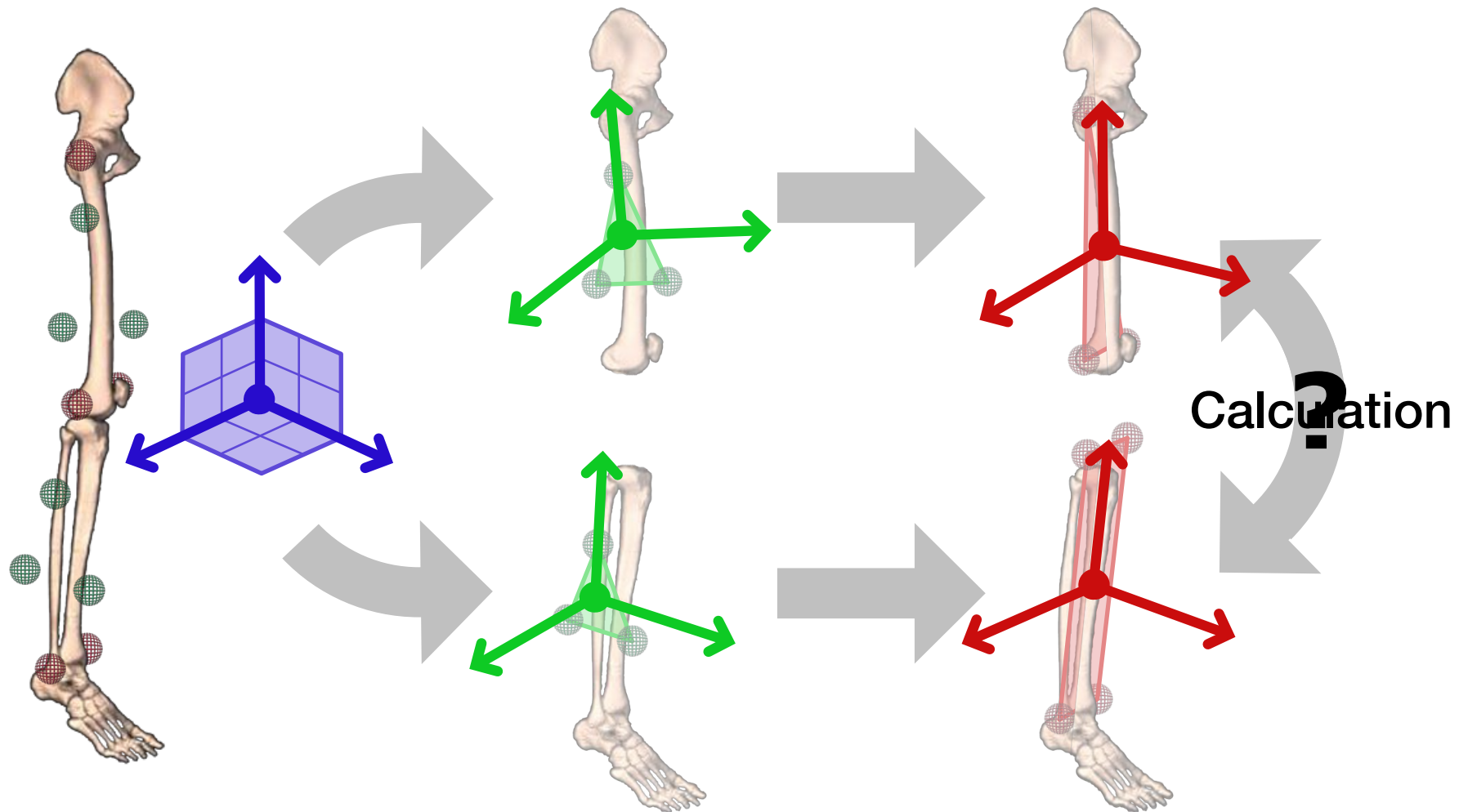
Simple

gh

nk

ot

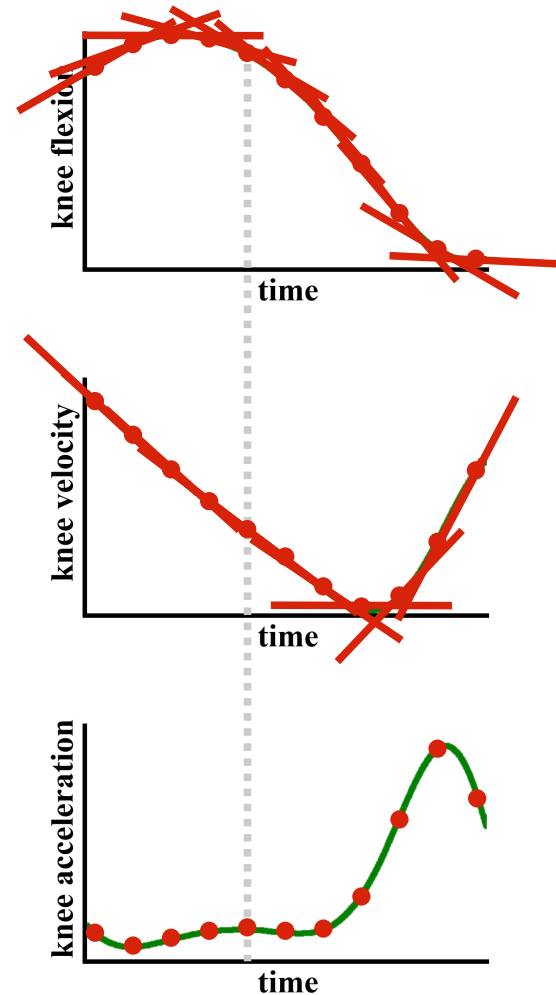
Measure Angle between coordinate frames using transformation matrix



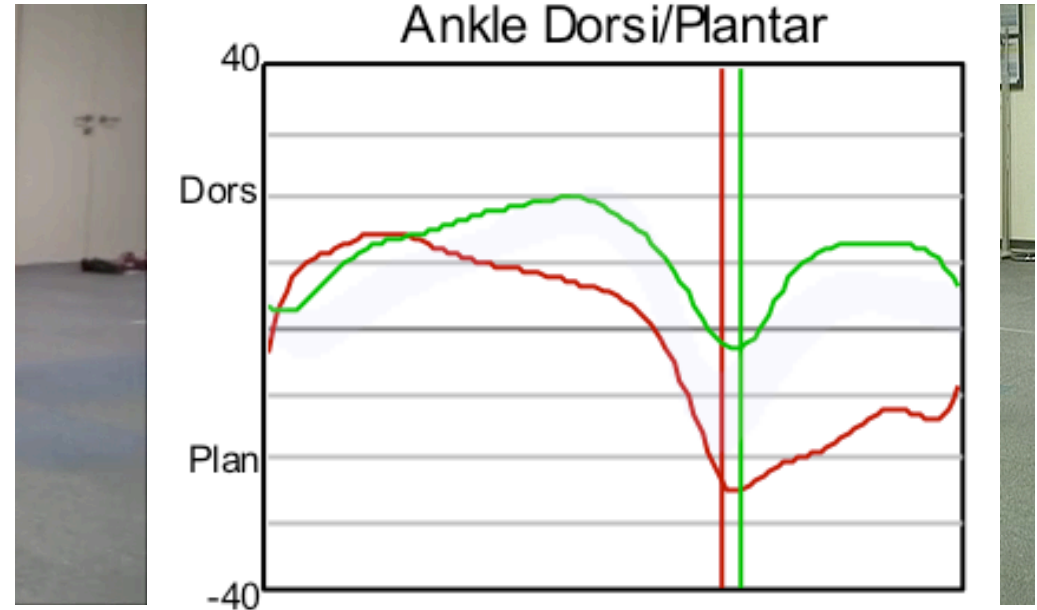
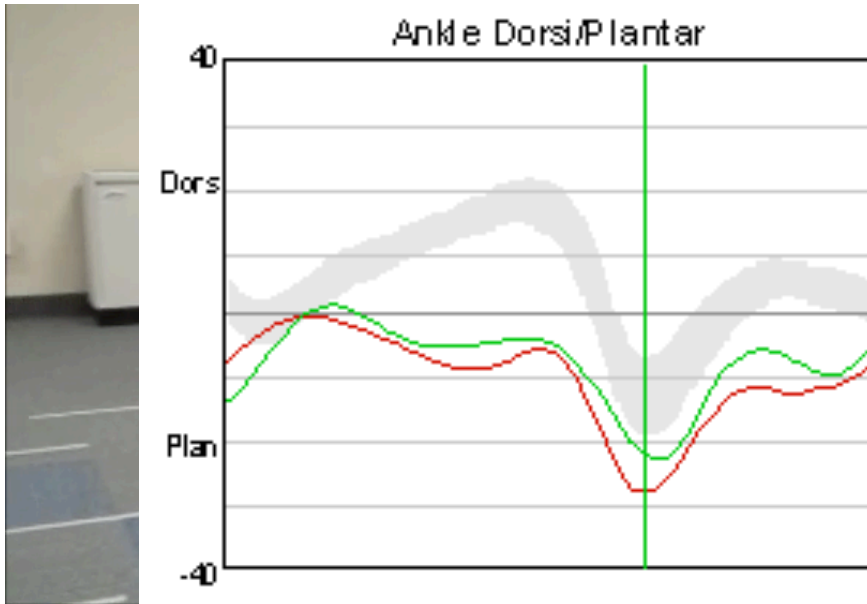
from Scott's presentation

(Inverse) Kinematics

- Linear
 - Position (p)
 - Velocity (v)
 - Acceleration (a)
- Joint
 - Orientation (θ)
 - Angular velocity (ω)
 - Angular acceleration (α)



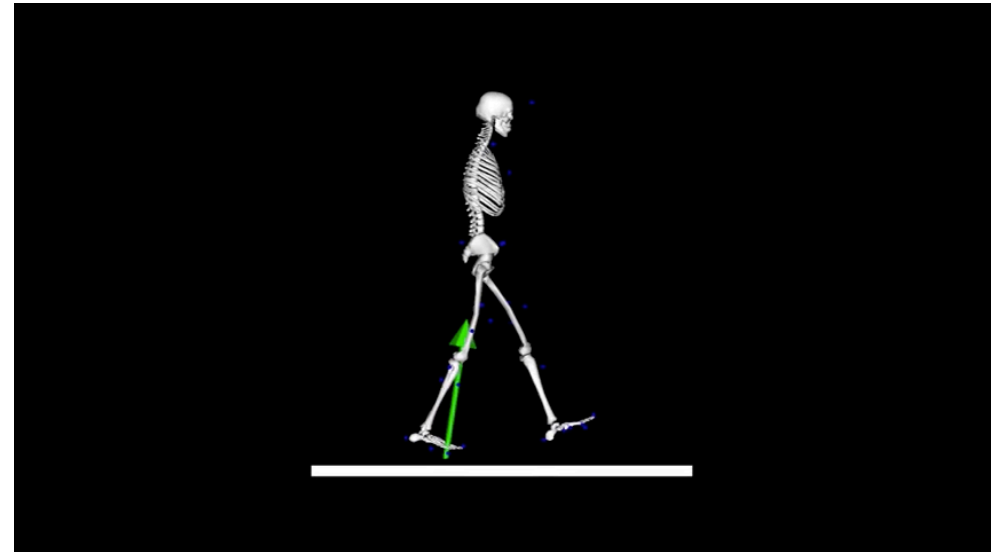
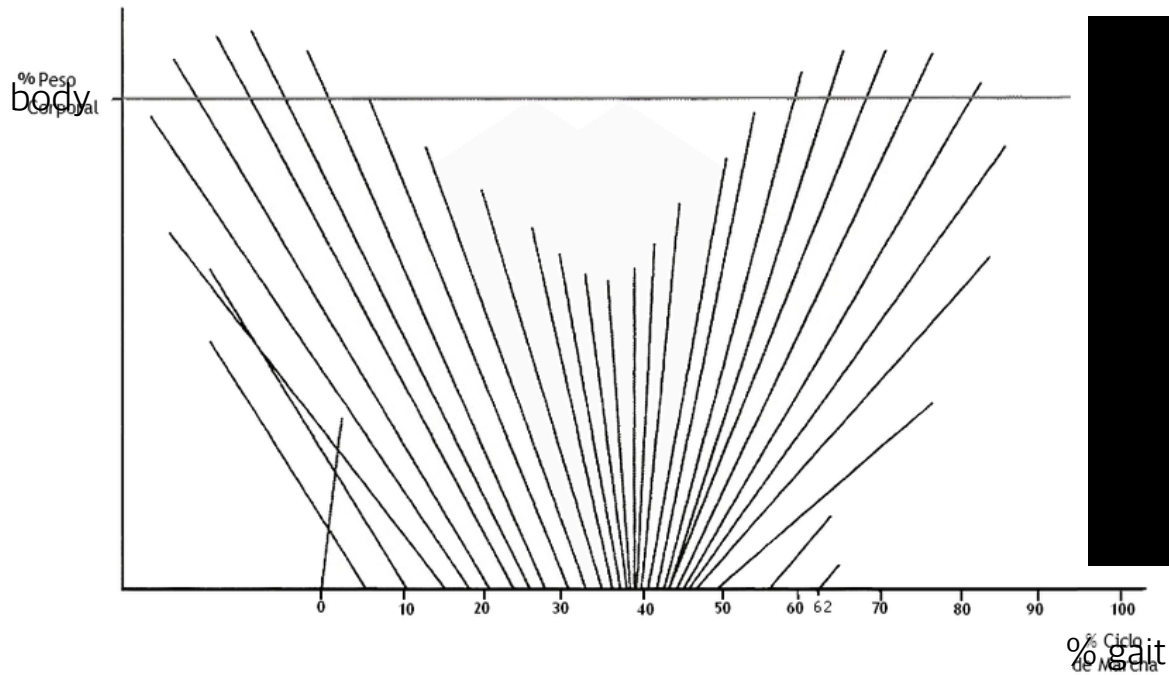
Equinus gait ?



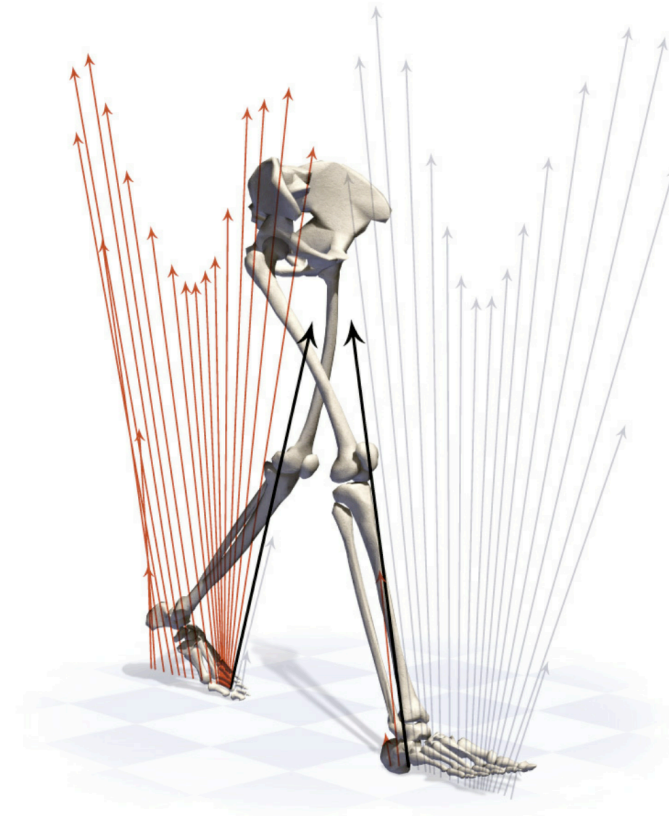
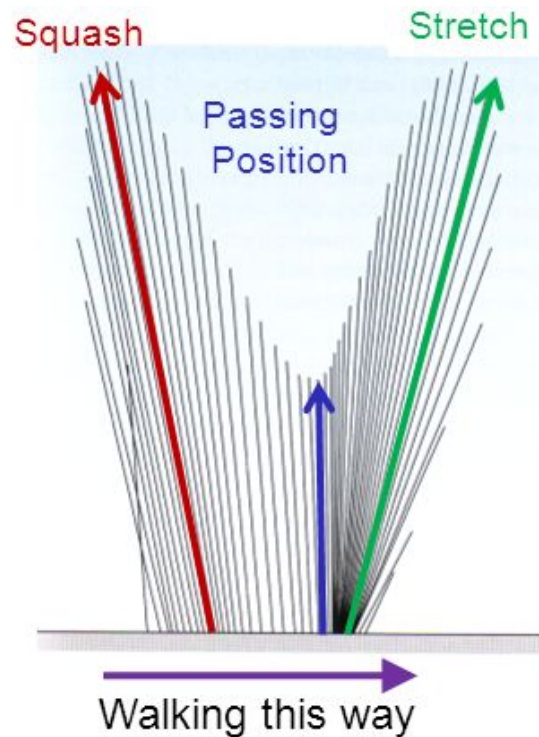
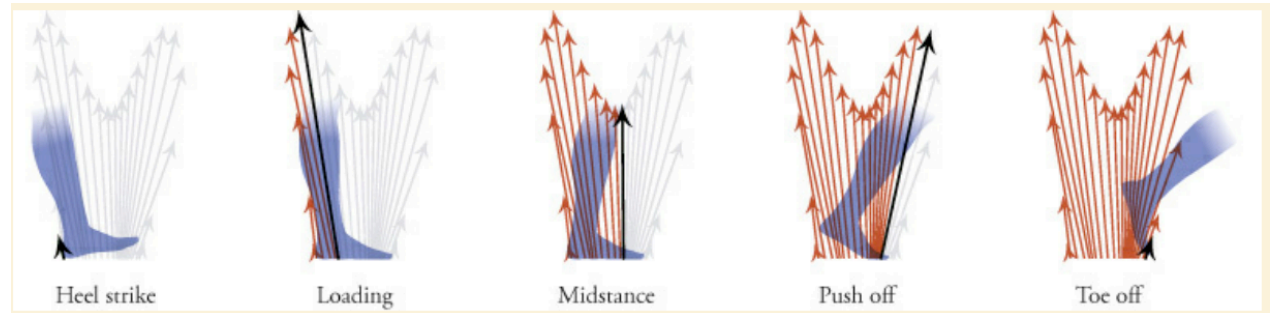
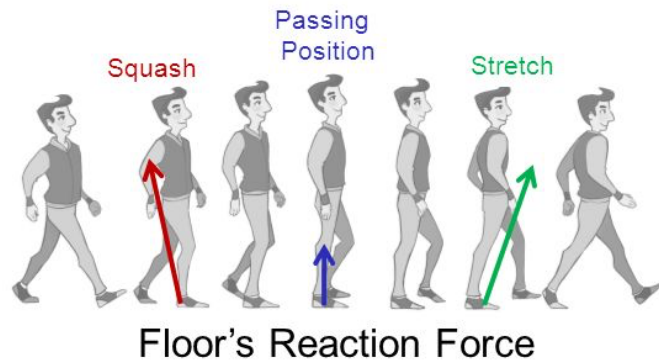
Inverse dynamics (Kinetics)

- How can we measure the joint moment(torque)? -

Ground reaction force

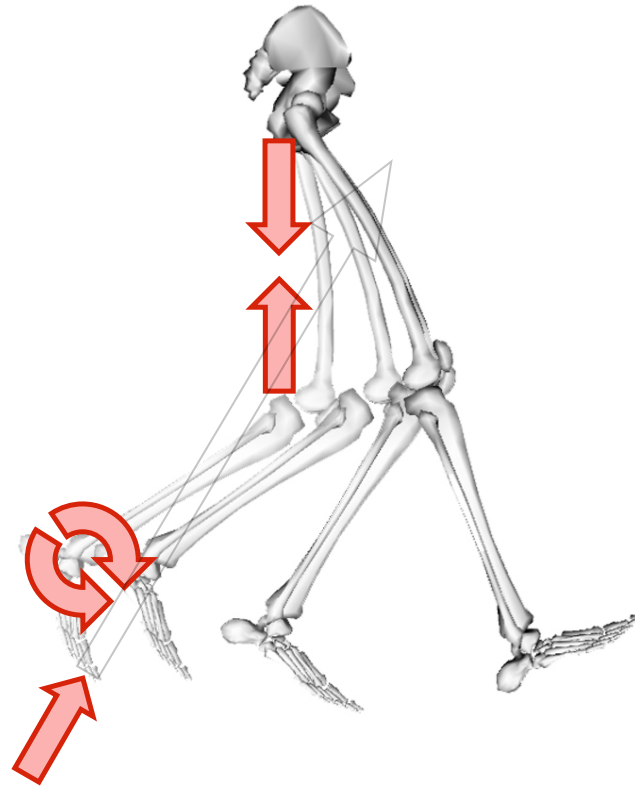


Ground reaction force

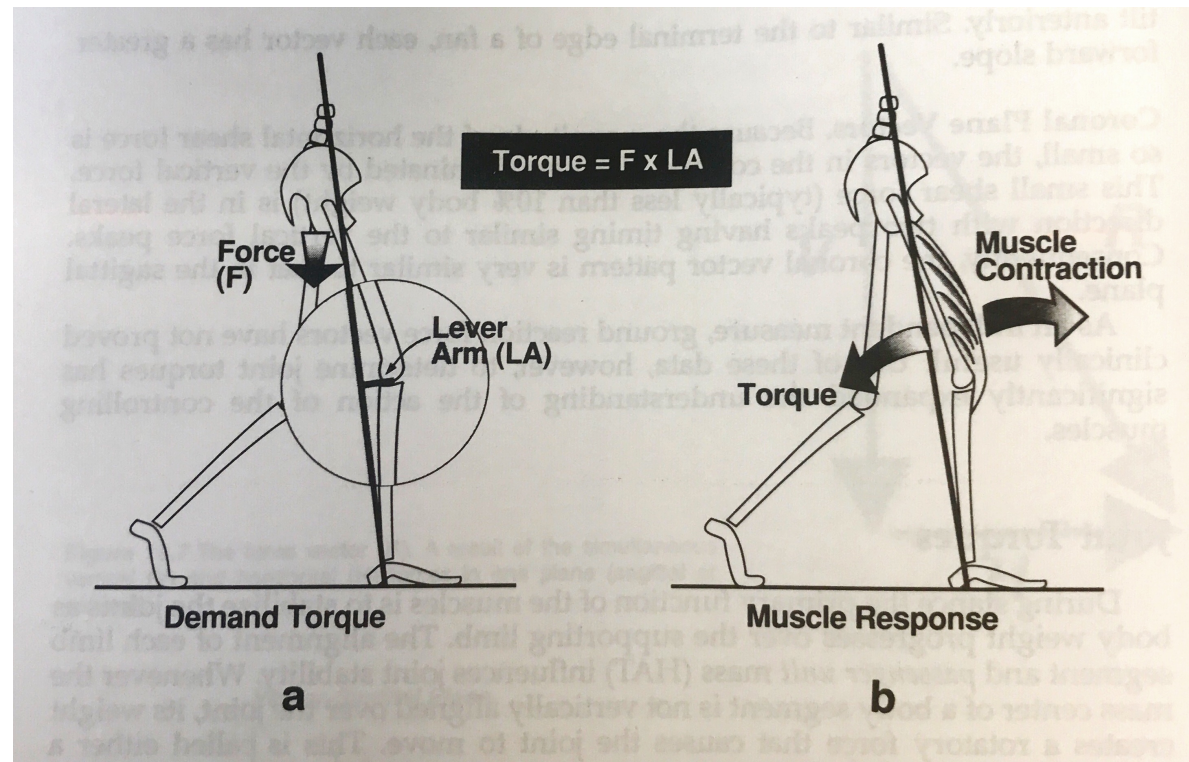


Inverse Kinetics

- Kinetics
 - Forces and torques cause the model to accelerate
- Force
 - Applied to points (e.g., ground reactions) or between points (e.g., muscles)
- Torque (moment)
 - Applied to a coordinate (e.g., joint torque)
 - **force x moment arm**



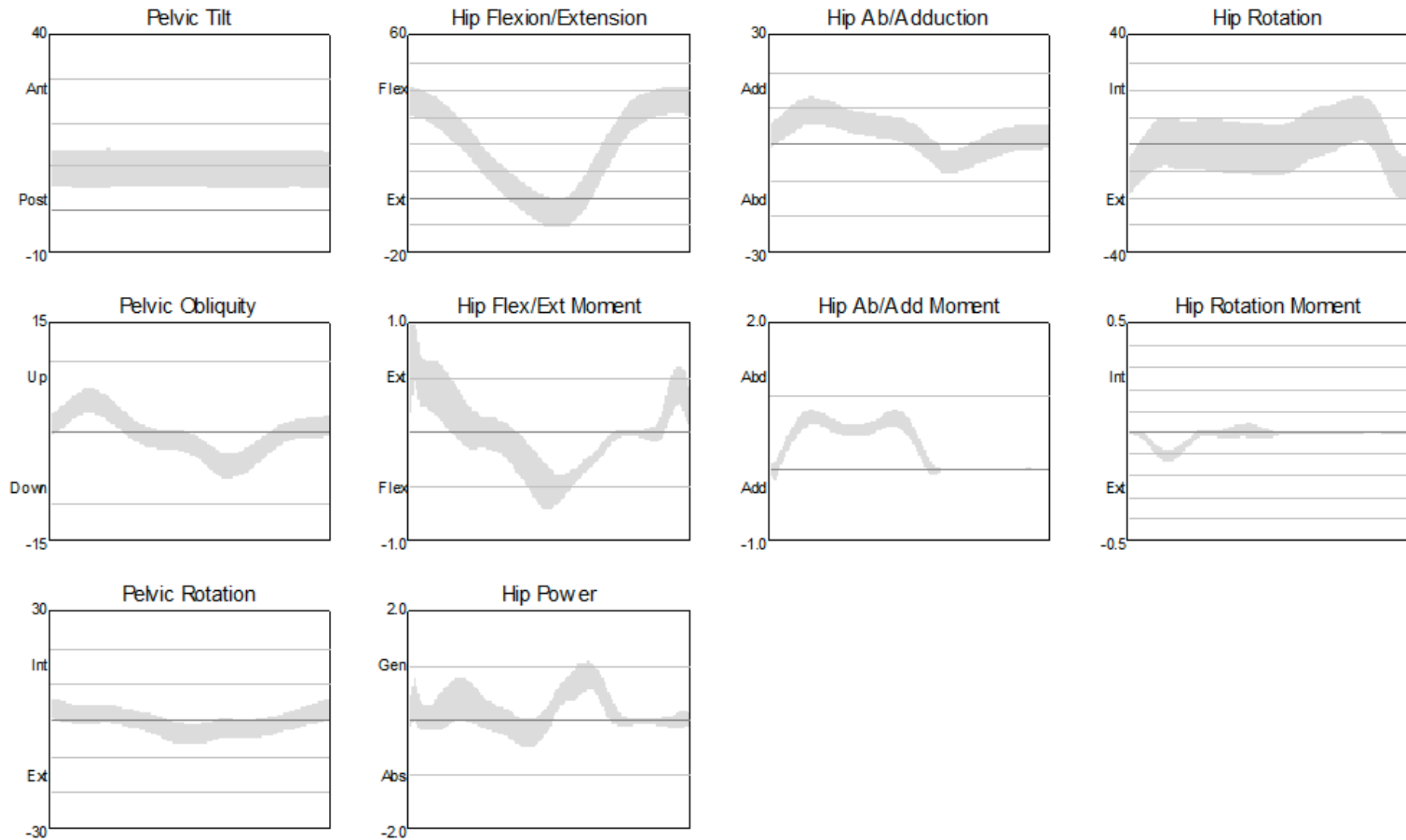
Inverse Kinetics



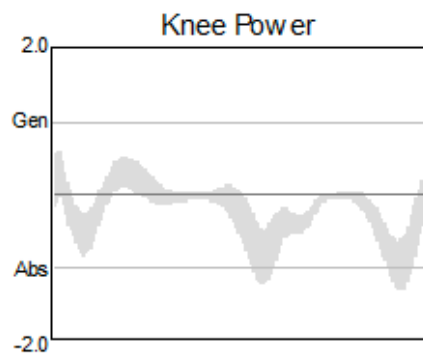
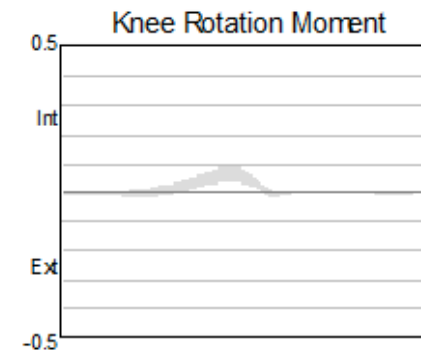
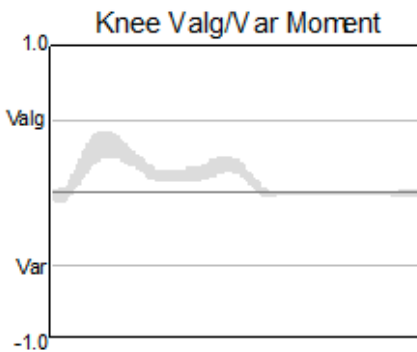
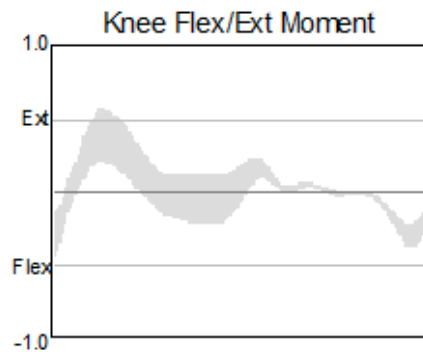
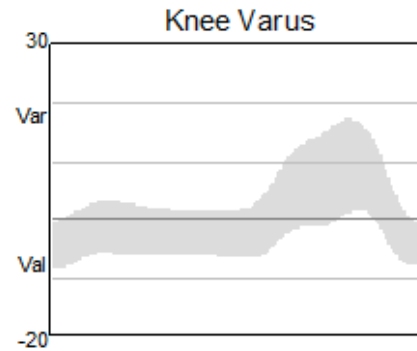
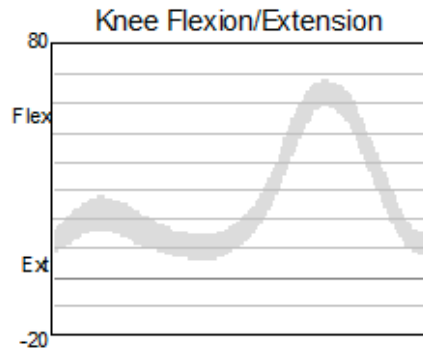
Motion = External torque (by GRF) + Internal torque (by body)

Internal torque (by body) = Motion - External torque (by GRF)

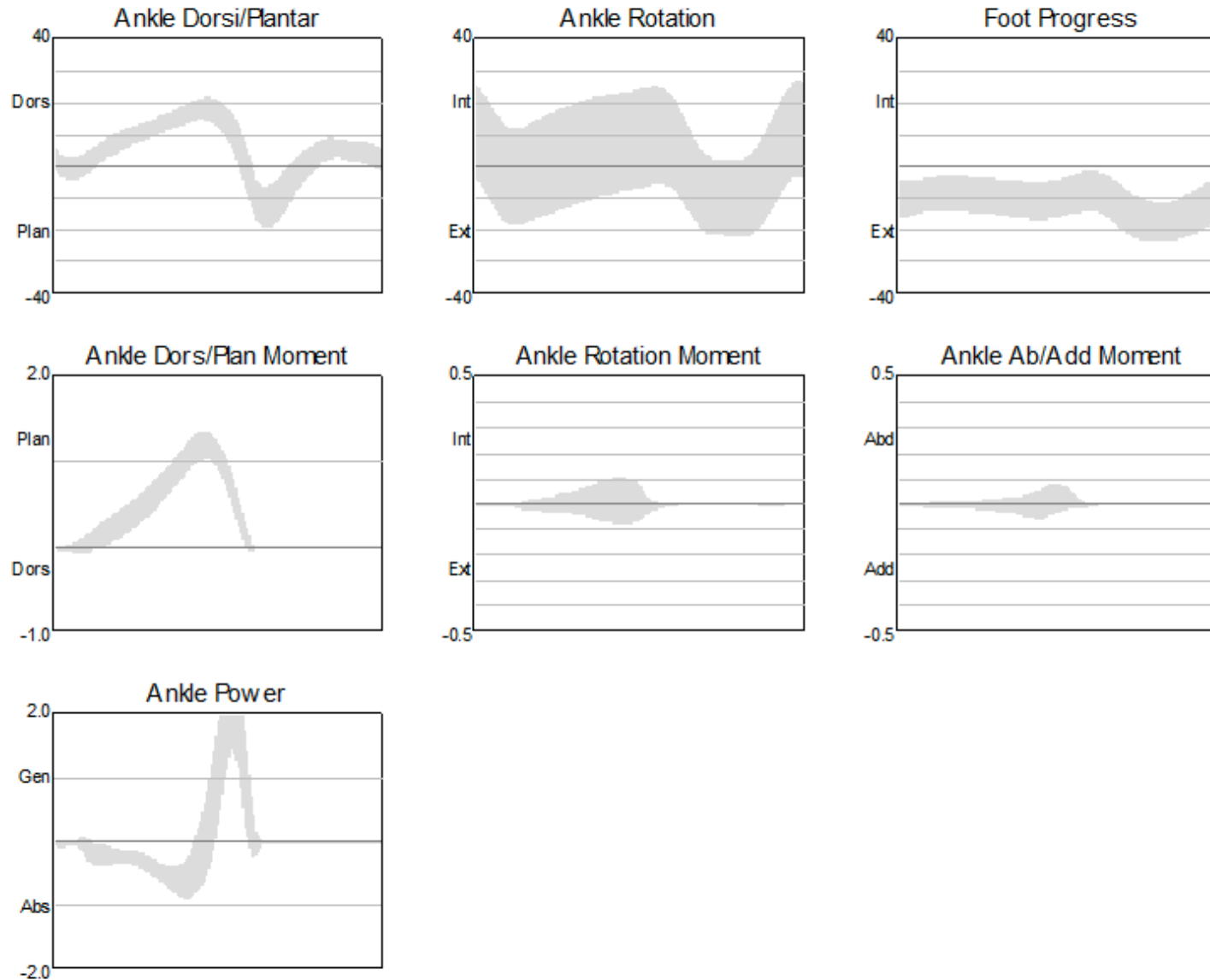
Normal gait analysis



Normal gait analysis



Normal gait analysis



“Thank you for listening.”

BMRR Laboratory (BioMechanics and Robotic Rehabilitation)

- <http://biomechanics.yonsei.ac.kr>
- bmrr.lab@gmail.com



Dong-wook Rha
Supervisor



Juntaek Hong
Supervisor



Beom Gi Yoo
PhD candidate



Da In Shim
PhD candidate



Joong-on Choi
MS candidate