How to compute muscle moment arm with Simbody

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OpenSim provides to its biomechanics users a calculation called “muscle moment arm” which captures to some degree the leverage of a particular muscle with respect to a particular joint, while in a particular configuration. For simple cases, this is the same as the conventional moment arm calculation in mechanical engineering. A straight-line muscle whose origin and insertion points connect two adjacent bodies connected by a pin joint is the simplest case. In practice, however, muscle may span several joints (wrist, neck, spine) and will follow contorted paths crossing over various curved bone surfaces. For these situations we need a careful definition of “muscle moment arm” that is analogous to the mechanical engineering concept and of use to biomedical researchers.

There are other related quantities that can easily be confused with moment arm, such as the amount of joint acceleration that a muscle can produce. That will be equivalent to moment arm in simple cases but confusingly different in more complex situations. Here we will give a precise definition of what we mean by “muscle moment arm” and, given that definition, how that quantity may be efficiently calculated. We will not attempt to address any deeper questions such as when you should be interested in moment arm or how you should use it.

# Assumptions

A muscle is considered to connect body A to body B via a minimum-length curved path connecting an “origin” point on body A to an “insertion” point on body B, possibly passing frictionlessly over wrapping surfaces on these or other bodies. No particular connectivity is assumed for these bodies in the multibody model of the skeleton. For example, there might be a patella with wrap surface hanging off one of the bodies and driven from an arbitrary mobility.

**Assumption 1**: The path includes both muscle and tendon segments whose relative lengths vary dynamically, but we are assuming that the total length *l* is just a kinematic quantity  (typically representing the shortest path) that can be calculated once the poses of all the bodies are known via specification of the generalized coordinates *q*. So for any given muscle we assume



It is critical that any motion of points at which the muscle applies forces be modeled physically so that muscle forces do the appropriate amount of work.

**Assumption 2**: Force generation by the muscle is completely characterized by a scalar tension  acting uniformly along the path, such that the set of spatial forces[[1]](#footnote-1) *F* applied by the muscle in a given configuration is just a linear function of *s*:



where *T*=*T*(*q*) is the muscle’s instantaneous “force transmission matrix”. We expect that a muscle element can efficiently compute *F* given *s*, although *T* is not explicitly available.

# Brief background

A few details are necessary for the derivation below.

1. Generalized speeds *u* are not always the same as time derivatives  of the generalized coordinates *q*, although they are closely related. This distinction will be important below because generalized forces are dual to the generalized speeds, but not to the generalized coordinate derivatives. In Simbody, the relationship is given by a block diagonal matrix N(*q*):



1. There is a dual relationship between forces and velocities when measured in the same basis. The portion of a body *B*’s spatial velocity (at *B*’s origin) due to generalized speed *ui* is:



where Jacobian , and . The dual of this relationship relates a spatial force  applied at body *B*’s origin to the generalized force *fi*:



and . For the dual relationship to hold, the generalized speeds and forces must be expressed in the same generalized basis.

# Definition of “moment arm”

Moment arm is a property of a given muscle about a particular angular quantity of interest we’ll call *θ*, measured at a particular configuration *q* of the multibody system. It is a scalar geometric quantity *r*=*r*(*q*), with units of length. *r* relates an infinitesimal change in muscle length *l* to the corresponding unitless change in angle *θ*, via the definition



Moment arm is defined only for angles *θ* which determine muscle length *l* kinematically, that is, we expect a virtual displacement *dθ* to produce a virtual length change *dl* that depends only on *q*, not on velocities, forces, or masses. All generalized coordinates *q* that can affect *θ* are thus assumed to be coupled; any that are not coupled explicitly by a constraint will be held constant during the moment arm calculation (that is, they are “coupled” with a coupling factor of 0).

An OpenSim user requesting a moment arm calculation will specify a muscle, and choose one of the available angular quantities for that muscle. Currently only a generalized coordinate subset is available for this purpose, so *θ* will always be one of the *q*’s in the model. When the angle of interest is actually the sum of several coupled generalized coordinates, one of them (called the *independent coordinate*) is scaled so that it reads as the total angle rather than just the angle it controls directly. Coupler constraints are added separately to enforce the desired cooperative motion of the other *dependent* *coordinates*. The algorithm below does not require this approach, but there must be a way to calculate *θ* from the *q*’s and  from the .

Note that a muscle path may cross several independent coordinates, such as a hip and knee angle. When moment arm is calculated for one of those coordinates, the other is held rigid (meaning again that it is seen as coupled, but with a coupling factor of 0). Muscles crossing wrist, ankle, neck, and spine may be modeled with a single independent coordinate measuring the total angle, while several dependent coordinates are coupled to it.

# Ways to calculate moment arm

Starting with the definition, there are a variety of ways to calculate moment arm differing in precision, implementation difficulty, and conceptual difficulty.

## Finite differencing

We can calculate *r*=*dl*/*dθ* directly by finite differencing. That is, we can make a small perturbation Δ*θ*, satisfy all position constraints, update geometric calculations, and measure the resulting change Δ*l*. The advantage of this method is that it directly implements the definition, and it is conceptually very simple. However, it has several drawbacks: it produces an approximate answer, and involves linearization difficulties due to the complex path geometry and the need to ensure satisfaction of the nonlinear position constraints. Also, because this is done at the position level it includes only holonomic constraints, and cannot account for nonholonomic constraints such as rolling.

## Velocity-level kinematics

An easier and exact computation is available using velocities, since we have



That is, if we can calculate  then we need only enforce  (for example), satisfy all velocity constraints, then calculate . This is probably the best way to calculate moment arm provided the operator  is available. Unfortunately, it can be difficult to calculate  so we would like to find an alternative.

## Partial velocity method

By assumption above, we have  so



for a row matrix *P*(*q*) whose *i*th entry is the scalar . If we can write  for some coupling matrix *C*(*q*) (a column with entries *ci*), then from equation we have



Then comparing with and noting that transposing a scalar doesn’t change it, we have



If we had an explicit representation of *P*, this would be a very nice way to calculate *r*. However, this would again depend on being able to calculate  which we’re assuming is difficult. Since generalized forces are dual to generalized speeds, we’ll look at how to use forces instead of velocities to calculate *r*.

## Generalized force method

Simbody can map body spatial forces *F* to generalized forces *f* via an operator that calculates



where *J* is the system Jacobian (partial velocity matrix) that maps generalized speeds to the body spatial velocities they produce. (This is due to the dual nature of generalized velocity and force bases.)

Assumption tells us how to calculate *F* from a given muscle tension scalar *s*, using the muscle’s force transmission matrix *T*. Substituting into :



The column matrix *JTT* maps tension to generalized force; the dual problem mapping generalized speeds to  is then ( proof?). From equation it follows that . Substituting into equation and using equation gives



This gives us the algorithm we need for calculating moment arm without knowing how to calculate  directly:

1. Determine the coupling matrix *C* for the angular quantity of interest *θ* (see below)
2. Apply unit tension *s*=1 to the muscle of interest and map to muscle forces *F*(*s*) using operator
3. Use the Simbody operator to map muscle forces *F*(*s*) to generalized forces *f*(*s*) (see below)
4. Use equation to compute *r*=*CTf* / *s* (see below)

### 1. Calculating the coupling matrix *C*

Set , use Simbody’s project() operator to find a least squares solution that satisfies the velocity constraints (this will change  as well). Determine the new value for , and call it . Now each , so  and we have determined .

Code example:

// Calculate coupling matrix C:

// Assume “mobod” is a mobilized body whose 0th mobility has been scaled

// so that its generalized coordinate is the angle theta.

state.updU() = 0;

mobod.setOneU(state, MobilizerUIndex(0), 1); // thetadot\_0 = 1

system.project(state, 1e-10,

yWeights, cWeights, yErrEst, // dummies; see below

System::ProjectOptions::VelocityOnly);

// Now calculate C.

const Vector C = state.getU() / mobod.getOneU(state, MobilizerUIndex(0)); // / thetadot\_1

state.updU() = 0;

// Note: you can declare these dummies for the project() call above.

const Vector yWeights(state.getNY(), 1);

const Vector cWeights(state.getNMultipliers(), 1);

Vector yErrEst;

### 3. Mapping spatial forces to generalized forces

If you can collect the muscle’s generated spatial body forces *F* into an array with an entry for each body (zero where the muscle does nothing), you can generate the equivalent generalized forces using Simbody’s oddly-named method calcInternalGradientFromSpatial().

Code example:

// Calculate the joint torques f equivalent to the muscle forces F, method 1:

Vector\_<SpatialVec> F; // Indexed by MobilizedBodyIndex

muscle.setTension(s);

// ... obtain F from the muscle somehow

Vector f;

matter.calcInternalGradientFromSpatial(state, F, f);

An alternative is to let Simbody gather up all the body and generalized forces produced by all force elements, and work with the difference between inactive and activated muscle.

Code example:

// Calculate the joint torques f equivalent to the muscle forces F, method 2:

Vector f0, f1, f;

// Start with the muscle off

muscle.setTension(0);

system.realize(Stage::Dynamics);

matter.calcInternalGradientFromSpatial(state,

system.getRigidBodyForces(state,Stage::Dynamics),

f0);

f0 += system.getMobilityForces(state,Stage::Dynamics);

// Now turn on the muscle

muscle.setTension(s);

system.realize(Stage::Dynamics);

matter.calcInternalGradientFromSpatial(state,

system.getRigidBodyForces(state,Stage::Dynamics),

f1);

f1 += system.getMobilityForces(state,Stage::Dynamics);

// f is the change in generalized forces due to the muscle

f = f1 – f0;

### 4. Calculating the moment arm

With C and f calculated as above, the moment arm calculation is easy:

Real momentArm = ~C \* f / s;

# Appendix: How to map generalized forces to torques

Assuming mass properties are available, we can test consistency between moment arm and the resulting dynamics. We can apply a muscle tension *s*, calculate moment arm *r* about some angular quantity *θ* as above, and also calculate generalized accelerations  and constraint multipliers *λ* using the equations of motion, that is, by calling realize(Acceleration) in Simbody. Then given  and *λ* we would like to determine the torque *τθ* that must have been applied across the rotational mobilities that contribute to *θ*, and verify that *τθ*=*rs*.

Assume that *θ* is defined as . That is, the angle of interest is determined by the sum of the individual angles at several mobilities. Then we can write where the summation is taken over the same mobilities as appear in the definition of *θ*. Note that the angles *θi* do not necessarily correspond to generalized coordinates, since OpenSim allows generalized coordinates to be scaled. Similarly, the are not generalized forces since those must be scaled to be consistent with the generalized speeds.

Denote the scaling of the *i*th generalized speed *wi* such that . Then we must have  because must have physically meaningful units. So now we can use inverse dynamics to calculate  and calculate .

The only remaining question is how to determine the scaling factors *w*. These come directly from the definition of the generalized speeds for a mobilizer:



Dropping superscripts and writing  shows that , thus  is the scaling factor that relates *u* to angular velocity in radian/s. Thus we have . Columns of *H* may be obtained via the getHCol() method of MobilizedBody:

const SpatialVec H\_PB\_G = mobod.getHCol(state, MobilizerUIndex(0));

Real wi = H\_PB\_G[0].norm(); // select the angular component, calculate magnitude

1. A spatial body force *FB* is a pair of vectors: a moment applied to body *B* and a force applied at the body *B* origin; *F* here is a stacked vector of such spatial body forces. [↑](#footnote-ref-1)