




MocoExtendProblem: Interface Between OpenSim and MATLAB for Rapidly Prototyping Direct Collocation Goals

Aravind Sundararajan^{1,2*}, Varun Joshi^{2*}, Brian Umberger^{3¶}, and Matthew O'Neill³

¹ Lyman Spitzer, Jr. Fellow, Princeton University, USA ² Institution Name, Country ³ Independent Researcher, Country ¶ Corresponding author * These authors contributed equally.

DOI: [10.xxxxxx/draft](https://doi.org/10.xxxxxx/draft)

Software

- [Review](#) 
- [Repository](#) 
- [Archive](#) 

Editor: [Open Journals](#) 

Reviewers:

- [@openjournals](#)

Submitted: 01 January 1970

Published: unpublished

License

Authors of papers retain copyright and release the work under a Creative Commons Attribution 4.0 International License ([CC BY 4.0](#)).

Summary

MocoExtendProblem (MEP) is a more convenient MATLAB framework for prototyping and developing direct collocation goals for OpenSim Moco. MEP features several tools for testing and prototyping and using novel MocoGoals without resorting to rebuilding all of opensim or generating an .omoco file from C++ and loading the problem into MATLAB. Instead, users can structure their custom goals, build these with the visual studio and the MEX compiler and add them to existing MATLAB scripts.

This repository features :

- A set of C++ and MATLAB scripts and models for prototyping and testing custom goals
- a build.m script that compiles goals in the custom_goals or custom_goals45 and procedurally constructs the c++/MATLAB and compiles the MEX interface.
- Compatibility with OpenSim 4.2-4.4 and 4.5
- The ability to include MEP as a submodule, build, and use valid custom goals
- Custom goals previously developed in our labs are in the custom_goals directory

Statement of need

OpenSim is an open-source software platform for biomechanical modeling and simulation (Seth et al., 2018). The platform enables researchers and healthcare professionals to investigate how biological and non-biological structures respond to different loads, postures and activities. It has been used to study a wide range of biomechanical problems, such as the mechanics of walking and running (e.g. Faleššie et al., 2019), the impact of injury or disease on movement (e.g. Johnson et al., 2022), and the effectiveness of rehabilitation exercises (Spomer et al, 2023).

Direct collocation is a numerical optimization method used in dynamic systems and control engineering. It involves representing the system dynamics as a set of algebraic equations, which are then discretized over time, and solved as a nonlinear optimization problem to obtain the optimal control inputs. The method aims to find a numerical solution that satisfies the system constraints and optimizes a performance measure. Optimization paradigms like direct collocation have begun to play a critical role in expanding our understanding of biological locomotion through the in-silico testing of novel therapies and predictive capabilities.

Within OpenSim is the software toolkit Moco (Dembia et al., 2020), which employs direct collocation with IPOPT (i.e. optimization software; Wächter and Biegler, 2006) in order to solve trajectory optimization problems that could range from tracking experimental motion capture

40 data for solving generalized coordinates, actuator controls, and kinetics to fully predictive
41 simulations. Moco employs CasADi (Andersson et al., 2019) to transform MocoProblem
42 consisting of control goals and constraints into sets of matrices for nonlinear optimization.
43 While direct collocation is powerful and OpenSim can be used to generate a broad range of
44 dynamically-consistent simulations, it can be daunting for some users to modify and rebuild
45 novel direct collocation goals.

46 We developed MEP so researchers, clinicians, and students without experience compiling
47 C++ can still write and test custom goals. By contrast, OpenSim's interfaces for MATLAB
48 are developed using SWIG, as opposed to MEX, which can be daunting for even seasoned
49 biomechanists. Running build.m will compile custom goals developed and placed in the
50 custom_goals directory, or if using OpenSim 4.5, MEP will search the custom_goals45. This
51 distinction for pre- and post- 4.5 MEP is to handle where scaling arguments are moved to the
52 abstract MocoGoal.

53 No further modifications to CMakeLists.txt are required; however cmake and msbuild.exe
54 from Visual Studio 2019 or higher needs to be added to the system PATH. build.m will
55 procedurally construct both extend_problem.m and ExtendProblem.cpp by parsing the header
56 files of the discovered goals within the custom_goals directory. Both ExtendProblem.cpp and
57 extend_problem.m generate bindings to instantiate custom goals placed in the custom_goals
58 directory. Custom Goals will be compiled with VS2019+ and then MATLAB's MEX compiler
59 is used to compile the MEX function. ExtendProblem.cpp leverages the C++ library mexplus
60 (Yamaguchi, 2014) to gain access to MEX entry points entry and exit points through C++
61 macros.

62 To incorporate extend_problem goals into an existing script, a C-style pointer to the instantiated
63 MocoProblem is passed as a constructor argument to the extend_problem.m class that wraps
64 the MEP MEX. Class methods of extend_problem.m (Figure 1; blue) are then used to add
65 custom goals to the MocoProblem.

MEP Framework organization. The end user runs the build.m script (orange) that subsequently calls methods in the utils folder (red) which are tasked with reading the custom_goals and custom_goals45 folder (green) and procedurally construct the mex and the interface class that calls the mex (blue). Each custom goal (green) is essentially handled as its own compiled plugin.

Figure 1: MEP Framework organization. The end user runs the build.m script (orange) that subsequently calls methods in the utils folder (red) which are tasked with reading the custom_goals and custom_goals45 folder (green) and procedurally construct the mex and the interface class that calls the mex (blue). Each custom goal (green) is essentially handled as its own compiled plugin.

66 To create a new goal with MEP: 1. copy one of the goals in the custom_goals folder 2. rename
67 all files to that of your custom goal's name 3. regex replace (or by hand) mentions of the
68 original copied goal name to that of your goal's name in each of the 5 files, being careful
69 to also modify the include guards in the dll and register types header files 4. Reimplement
70 initializeOnModelImpl, calcIntegrandImpl, calcGoalImpl such that they describe your custom
71 goal.

72 In order to run a new custom goal, obtain the C-style pointer from OpenSim's existing SWIG
73 interface and pass this as a constructor argument to extend_problem.

```
cptr = uint64(problem.getCPtr(problem));
ep = extend_problem(cptr);
ep.addMocoCustomGoal('custom_goal',weight,power,divide_by_distance);
```

74 This paradigm has implications for OpenSim and MATLAB developers beyond the scope of
75 just incorporating novel MocoGoals; these same tools can be used to develop other tools or
76 expand other classes and easily incorporate them into existing MATLAB-OpenSim scripts. We

77 have posted all tools, instructions and simulation results related to this project on GitHub and
78 SimTK.org/MEP.

79 Showcases

80 To demonstrate the utility of this framework, we utilized a two-dimensional (2-D) full-body
81 human musculoskeletal model operated through the MATLAB-OpenSim API to simulate a
82 half walking gait cycle (Denton and Umberger, 2023). The base code uses Moco's built-
83 in MocoControlEffortGoal and MocoAverageSpeedGoal to generate tracking and predictive
84 simulations of a dynamically-consistent walking step that minimizes the sum of the squared
85 control effort, at an average speed of 1.3 m s⁻¹. Additionally each objective function has an
86 implicit acceleration minimization and auxiliary derivative cost term which help to smooth
87 model kinetics and remove transient oscillations in ground reaction forces.

88 Since Moco lacks any built-in gait stability goals, we developed three custom stability goals
89 using MEP to prototype and compile into a new `extend_problem` class that adds these to an
90 existing MocoProblem. The first is a base of support (BOS) criterion in which the center
91 of mass is optimized to lay between the average of the two mass centers for the calcaneus
92 projected to the ground reference frame, the second is a zero-moment-point goal (ZMP)
93 criterion that assumes the model is an inverted pendulum and the center of mass tracks the
94 computed zero-tilting moment location, and the third is a marker acceleration minimization
95 goal (ACCmarker) that minimizes the explicit accelerations of the marker's station location.

96 MEP's `build.m` was used to generate an `extendproblem.cpp` and `extend_problem.m` class which
97 wraps the custom goal to create a new, multi-objective function based on the sum of squared
98 control effort + stability criteria, such that:

99 EQUATIONS HERE:

100 The results of each multi-objective predictive simulation, in which the stability criterion was
101 compiled using MEP, is shown against the results from a tracking simulation (Figure 2). The
102 tracking simulation objective cost was a weighted sum of the tracking error (i.e. squared sum
103 of simulation from experimental kinematic and ground reaction force data) and sum of the
104 squared control efforts.

Sagittal plane hip, knee and ankle angles (a-c), vertical and A-P ground reaction forces (d-e),
the 11 degree-of-freedom, 18 muscle sagittal plane human walking model used for tracking
and predictive simulations (f).

Figure 2: Sagittal plane hip, knee and ankle angles (a-c), vertical and A-P ground reaction forces (d-e),
the 11 degree-of-freedom, 18 muscle sagittal plane human walking model used for tracking and predictive
simulations (f).

	Objective cost	Effort cost	Smoothing cost	Stability cost
J_{BOS}	3.048285	2.234377	0.008309	0.795659
J_{ZMP}	3.384394	2.679968	0.008816	0.686290
J_{accel}	3.814449	3.680096	0.010208	0.114528

105 [Table 1: Objective cost and term breakdown for three predictive simulations using MEP.]

106 Citations

107 Citations to entries in `paper.bib` should be in [rMarkdown](#) format.

108 If you want to cite a software repository URL (e.g. something on GitHub without a preferred
109 citation) then you can do it with the example BibTeX entry below for Smith et al. (2020).

110 For a quick reference, the following citation commands can be used: - @author:2001 ->
111 "Author et al. (2001)" - [@author:2001] -> "(Author et al., 2001)" - [@author1:2001;
112 @author2:2001] -> "(Author1 et al., 2001; Author2 et al., 2002)"

113 #Funding

114 This work was supported by the National Science Foundation (BCS 2018436 and BCS 2018523)

115 References

116 Smith, A. M., Thaney, K., & Hahnel, M. (2020). Fidget: An ungodly union of GitHub and
117 figshare. In *GitHub repository*. GitHub. <https://github.com/arfon/fidget>

DRAFT