

An Open-Source OpenSim Oculomotor Model for Kinematics and Dynamics Simulation

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Abstract

Studying human eye movements has significant implications for improving our understanding of the oculomotor system and treating various visuomotor disorders. An open-source musculoskeletal model of the human eye, that can be used for kinematics and dynamics analysis, is constructed based on the data reported in literature and made publicly available¹. The model is implemented in OpenSim, which is an open-source framework for modeling and simulation of musculoskeletal systems. The calibration of the model parameters is based on physiological measurements of the human eye. The model incorporates an eye globe, orbital suspension tissues and six extraocular muscles. The excitation and activation patterns for a variety of targets can be calculated using the proposed closed-loop fixation controller that drives the model to perform saccadic movements in a forward dynamics manner. The controller minimizes the error between the desired saccadic trajectory and the predicted movement. Consequently, this model enables the investigation muscle activation patterns during static fixation and analyze the dynamics of various eye movements.

¹SimTK project: <https://simtk.org/projects/eye>

Introduction

Rapid and accurate eye movements are crucial for coordinated direction of gaze [Lee and Terzopoulos \(2006\)](#). Studying human eye movement has significant implications for improving our understanding of the oculomotor system and treating visuomotor disorders. Over the past decades, biomechanics simulation has provided the means to analyze different human movements [Delp et al. \(2007\)](#). The same principles can be used to analyze visual tasks by modeling the musculoskeletal properties of the oculomotor system. Consequently, this model can be used to investigate muscle activation patterns during static fixation, analyze the dynamics of various eye movements, calculate metabolic costs and simulate eye disorders, such as different forms of strabismus. Furthermore, it can be easily integrated with available full body models in order to analyze the relation between the vestibular and oculomotor systems.

Saccadic movements are generated from a coordination of the six **Extraocular Muscles (EOMs)**. Clinical trials have provided a profound knowledge on the properties of the **EOMs** and their line of action on the eye globe [Robinson et al. \(1969\)](#), the resistive tension of the surrounding tissues [Collins et al. \(1981\)](#) and the length-tension relationship of the muscles [Iskander et al. \(2018\)](#). Various computational models of the extraocular muscles and orbital mechanics have been proposed, which provide insight and scientific bases for oculomotor biomechanics, control of eye movement and binocular misalignment. These models focus on the realism of muscle behavior and they were based on the viscoelastic properties and physiological data **EOMs**.

The first 3D biomechanical model was developed by [Robinson \(1964\)](#); [Robinson and Fuchs \(1969\)](#), who simplified the formulation by only considering the elasticity of the **EOMs** ignoring their dynamics. The model incorporates anatomically realistic muscle paths and empirical innervation-length-tension relationships. To study the neural control of rapid saccadic movements, models using anatomical and mechanical properties of **EOMs** have been developed by accounting for the nonlinear muscle dynamics [Thelen et al. \(2003\)](#); [Millard et al. \(2013\)](#). Such models, having the advantage of supporting dynamics simulation, are used in conjunction with brain level controllers [James et al. \(2018\)](#).

Methods

Eye Modeling

The eye model consists of the eye globe, three pairs of **EOMs** and the connective passive tissues. The size of an emmetropic human adult eye is approximately 0.0242m (transverse, horizontal), 0.0237m (sagittal, vertical), 0.022 – 0.0248m (axial, anteroposterior) with no significant difference between sexes and age groups. In the transverse diameter, the eye may vary from 0.021m to 0.027m, thus it can be approximated by a solid sphere of radius $r = 0.012\text{m}$. The weight of an average human eye is $m = 0.0075\text{kg}$ and the moment of inertia can be calculated assuming a spherical homogeneous and isotropic model $I = 2/5mr^2$. The eye has three rotational **Degrees of Freedom (DoFs)**, namely incyclotorsion-excyclotorsion (x -axis), adduction-abduction (y -axis) and supraduction-infraduction (z -axis).

Muscle Modeling

The six **EOMs**, including four rectus muscles and two oblique muscles, are controlled by the cranial nerves so as to track a visual target and to stabilize the image of the object. The **Lateral Rectus (LR)** and **Medial Rectus (MR)** muscles form an antagonistic pair that produce horizontal eye movements. The **Superior Rectus (SR)** and **Inferior Rectus (IR)** muscles form the vertical antagonist pair, which mainly controls vertical eye movement and also affects rotation about the horizontal plane and the line of sight (secondary action) due to insertion positions. The **Superior Oblique (SO)** muscle passes through the cartilaginous trochlea attached to the orbital wall, which reflects the **SO** path by 51 deg. The **Inferior**

Oblique (IO) muscle originates from the orbital wall anteroinferior to the globe center and inserts on the sclera posterior to the globe equator. The primary actions of **SO** and **IO** cause rotation of the globe around the visual axis and vertical movement.

The model relies on the passive pulley assumption. **Table 1** shows the positions of the origin, insertion and passive muscle pulleys for the **EOMs**, defined in the local body coordinates of the eye globe. The data are based on physiological measurements [Iskander et al. \(2018\)](#), with some minor modification so as to prevent unrealistic muscle-surface penetration. Since no position was documented for the origin of the **SO**, a point close to the origins of the rectus muscles was chosen to match the fiber length in the primary position of the **SO** muscle.

Table 1: Muscle path points for the six **EOMs** defined in the local frame of the eye globe (dimensions are given in meters).

Muscle	Origin			Pulley			Insertion		
	O_x	O_y	O_z	P_x	P_y	P_z	I_x	I_y	I_z
LR	-0.034	0.0006	-0.013	-0.0102	0.0003	0.012	0.0065	0	0.0101
MR	-0.030	0.0006	-0.017	-0.0053	0.00014	-0.0146	0.0088	0	-0.0096
SR	-0.0317	0.0036	-0.016	-0.0092	0.012	-0.002	0.0076	0.0104	0
IR	-0.0317	-0.0024	-0.016	-0.0042	-0.0128	-0.0042	0.00805	-0.0102	0
SO	0.0082	0.0122	-0.0152	-0.030834	0.001145	-0.01644	0.0044	0.011	0.0029
IO	0.0113	-0.0154	-0.0111	-0.00718	-0.0135	0	-0.008	0	0.009

The Millard muscle model [Millard et al. \(2013\)](#) has been adopted for the modeling of the **EOMs**, permitting parameterization of the characteristic curves according to the experimental measured data. The muscles were modeled using the rigid tendon assumption that ignores the elasticity of the tendon. This means that the series element of the muscle model is not included (the tendon length l^T is equal to the tendon slack length l_s^T). **EOMs** are considered parallel-fibered muscles, so the pennation angle is zero ($\alpha = 0$). The values for the maximum isometric force f_o^M , optimal fiber length l_o^M and tendon length l^T are presented in **Table 2**.

Table 2: Millard muscle parameters for the **EOMs**.

Muscle	Maximum Isometric Force (N)	Optimal Fiber Length (m)	Tendon Slack Length (m)	Maximum Contraction Velocity (m / s)
LR	1.4710	0.04898	0.0084	3.8483
MR	1.5740	0.04084	0.0038	4.6155
SR	1.1768	0.04487	0.0054	4.2009
IR	1.4269	0.04549	0.0048	4.1437
SO	0.6031	0.03956	0.0265	4.7648
IO	0.5590	0.04110	0.0015	3.5863

The **Force-Length (F-L)** and **Passive-Force-Length (F-PE)** characteristic curves of the **EOMs** differ significantly from those of a skeletal muscle. As shown in **Figure 1**, we can fine-tune the curve parameters so as to fit the experimental data available for the **LR** muscle. The values for the **F-L** and **F-PE** characteristic curves are summarized in **Tables 3** and **4**, respectively.

EOMs have a higher fraction of fast twitch fibers and thus different **Force-Velocity (F-V)** behavior, due to different structures compared to skeletal muscles. Despite that, the default Millard **F-V** curve was used for the six **EOMs**, since the behavior of the selected muscle model depends heavily on the

Table 3: Parameters of the **F-L** characteristic curve for the **EOMs**.

Parameter	Value
min norm active fiber length	0.55
transition norm fiber length	0.7
max norm active fiber length	1.8
shallow ascending slope	2.4
minimum value	0.0

Table 4: Parameters of the **F-PE** characteristic curve for the **EOMs**.

Parameter	Value
strain at zero force	-0.18
strain at one norm force	0.4

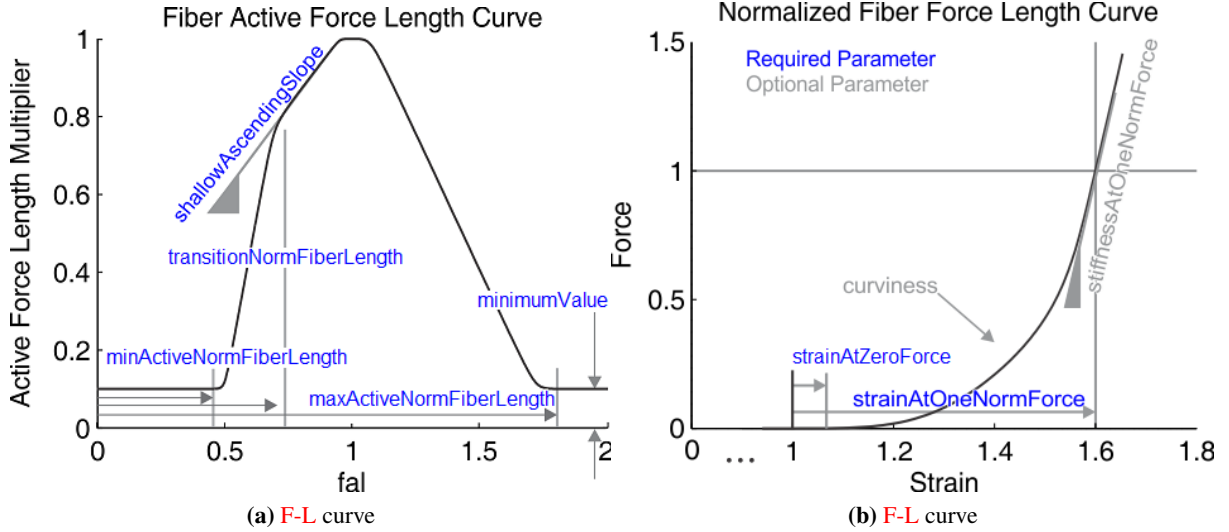


Figure 1: The **F-L** and **F-PE** curve definition for the Millard muscle model as implemented in OpenSim.

maximum contraction velocity v^{\max} . The maximum muscle contraction velocity is tuned so as to match the peak velocity of saccadic eye movement $\omega^{\max} = 15.7\text{rad/s}$ ($900^\circ/\text{s}$). Following this definition, the maximum muscle contraction velocity is given in optimal fiber length per seconds and it is thus different for each **EOMs**, as their optimal fiber length is different ($v^{\max} = \omega^{\max} r / l_o^M$). Furthermore, since the optic nerve is much shorter than the average muscle nerve, activation and deactivation delays ($\tau_a = \tau_d = 5\text{ms}$) are smaller. Finally, two separate wrapping spheres for the rectus muscles and the oblique muscles were created, to avoid abnormal changes on the **F-L** curve as the eye rotates.

Passive Connective Tissues

The passive connective tissues apply a restoring force, which brings the eye back to the central position when the net force from the **EOMs** is zero. These tissues include all non-muscular suspensory tissues, such as Tenon's capsule, the optic nerve, the fat pad and the conjunctiva. The force-displacement curve of the net elasticity can be represented as

$$f_t = -k_p q - k_c 10^{-3} q^3 - k_v * \dot{q} \quad (1)$$

where, f_t is the passive tissue forces, $k_p = 0.002225\text{Nm/rad}$, $k_c = 34.5297\text{Nm/rad}^3$ and $k_v = 0.002\text{Nm/(rad/s)}$ the constants and $\dot{q} \in \mathbb{R}^3$ the rotational coordinates of the model [Collins et al. \(1981\)](#). These forces are modeled using OpenSim's expression based coordinate force.

Results

Fixation Controller

A fixation controller was implemented as a custom OpenSim plugin. The parameters of the controller are: the desired horizontal θ_H and vertical θ_V fixation angles (in degrees), the saccade onset and velocity (in degrees), and the gains of **Proportional Derivative (PD)** tracking controller (k_p , k_d). A sigmoid function is used for generating smooth saccade trajectories

$$\begin{aligned}\theta_d(t) &= \frac{a}{2} (\tanh(b(t - t_0)) + 1) \\ \dot{\theta}_d(t) &= \frac{ab}{2} (\tanh^2(b(t - t_0)) - 1)\end{aligned}\tag{2}$$

where $\theta_d(t)$ and $\dot{\theta}_d(t)$ represent the desired orientation and velocity at time t , a the magnitude of the trajectory, b the slope and t_0 a time shift constant. Provided a fixation goal θ_g , a desired saccade velocity $\dot{\theta}_g$ and a saccade onset t_g the parameters of the sigmoid function are defined as follows $a = \theta_g$, $b = 2\dot{\theta}_g/\theta_g$ and $t_0 = t_s$. The **PD** tracking controller has the following form

$$\ddot{\theta}(t) = k_p(\theta_d(t) - \theta(t)) + k_d(\dot{\theta}_d(t) - \dot{\theta}(t)).\tag{3}$$

The sign and magnitude of $\ddot{\theta}(t)$ both for the horizontal and vertical displacement of the fixation target is used to actuate the corresponding muscles in order to achieve the desired goal. **Figure 2** presents an instance of the model during simulation with the corresponding muscles activated. **Figure 3** depicts the simulated coordinates, speeds and estimated **EOMs** activations that reproduce the desired saccade trajectory for different model parameters.

Conclusion

A realistic oculomotor model representing the motility of a normal human eye was presented and made publicly available. The parameters of the model were calibrated using available experimental measured data. The model can be used for kinematics and dynamics analysis or as a tool for obtaining the muscle activations that generate a desired saccade, using a closed-loop fixation controller in a **Forward Dynamics (FD)** manner. There is of course space for further improvement, which will enhance the accuracy and the predictability of the proposed computational model. In this study, we didn't attempt to model the muscle pulleys **Kono et al. (2002)**, which vary as a function of the model coordinates. Therefore, the users should consider performing further validation of the eye model based on the requirements of the targeted utility and the variables of interests.

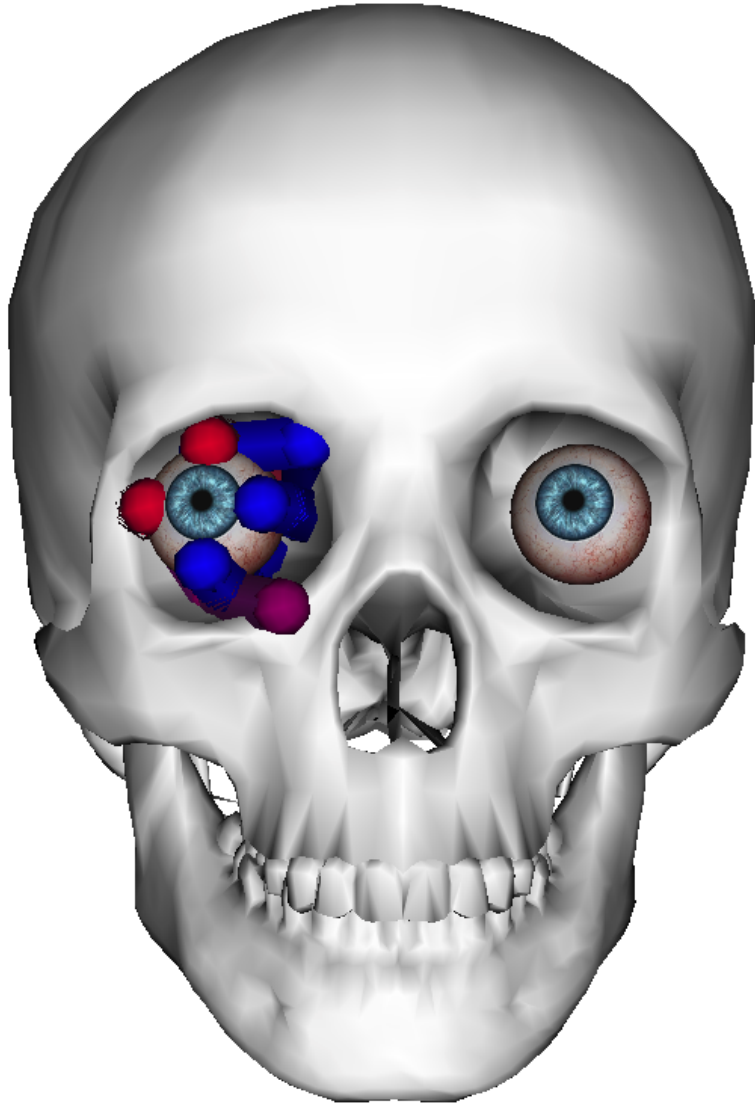
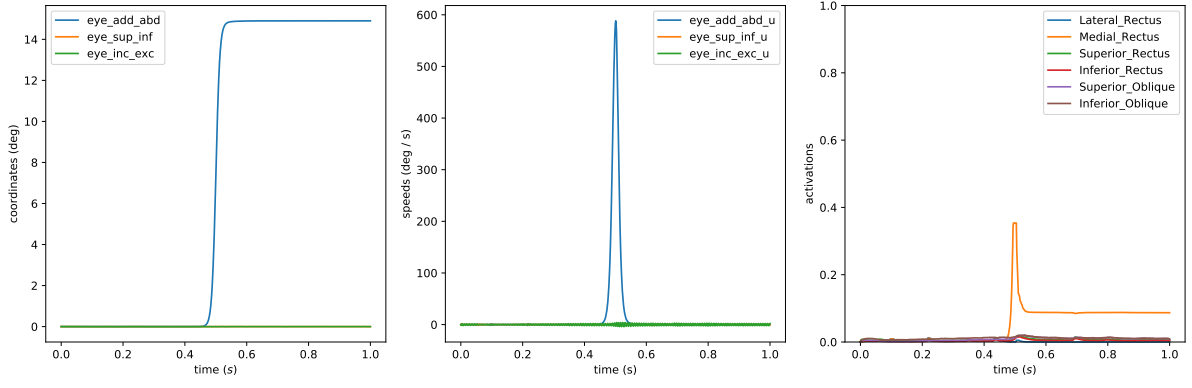
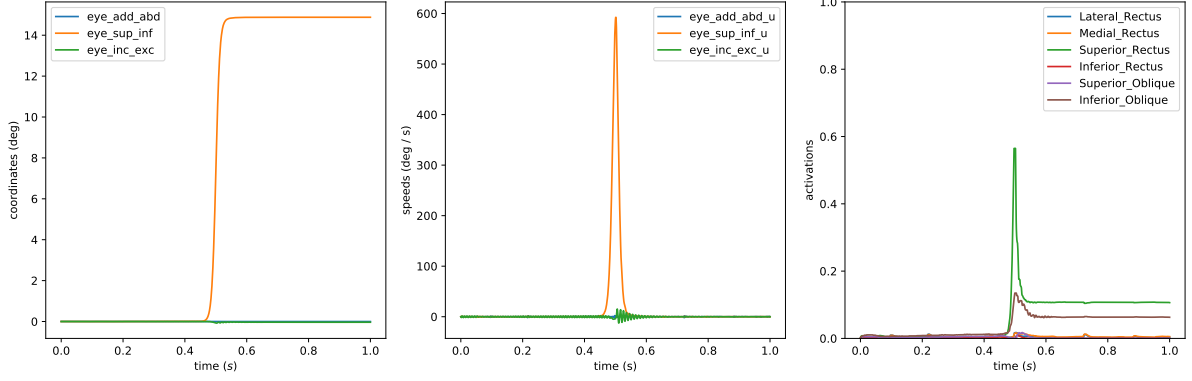


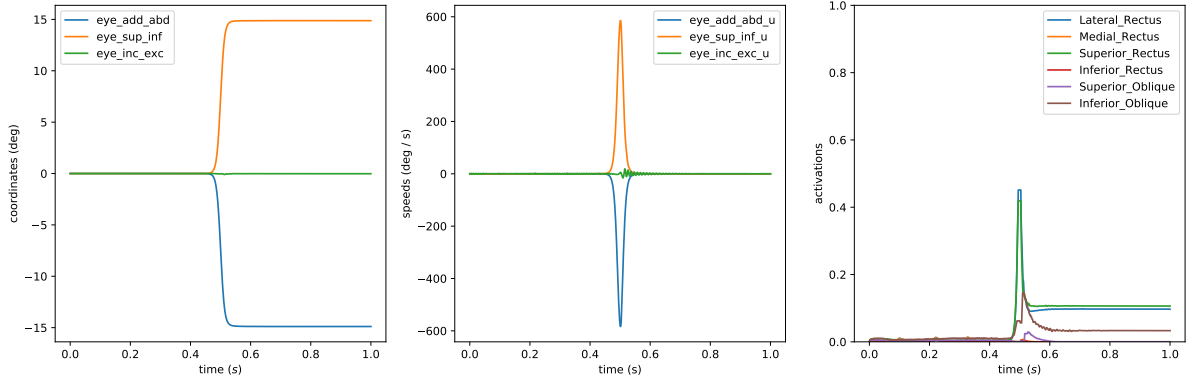
Figure 2: Model with a fixation at $\theta_H = -15^\circ$, $\theta_V = 15^\circ$ during simulation. Blue denotes low and red high muscle activation levels.



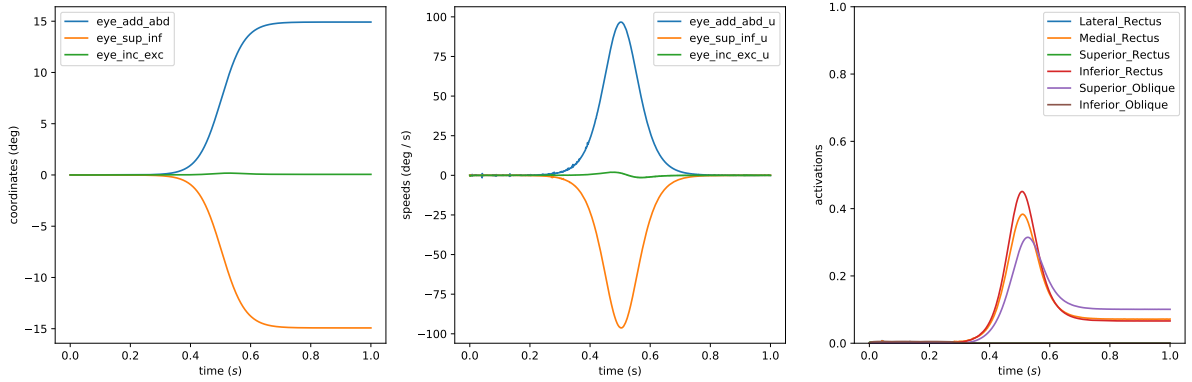
(a) $\theta_H = 15^\circ$, $\theta_V = 0^\circ$, $b = 600^\circ/\text{s}$ and $k_v = 0\text{Nm}/(\text{rad}/\text{s})$



(b) $\theta_H = 0^\circ$, $\theta_V = 15^\circ$, $b = 600^\circ/\text{s}$ and $k_v = 0\text{Nm}/(\text{rad}/\text{s})$



(c) $\theta_H = -15^\circ$, $\theta_V = 15^\circ$, $b = 600^\circ/\text{s}$ and $k_v = 0\text{Nm}/(\text{rad}/\text{s})$



(d) $\theta_H = -15^\circ$, $\theta_V = 15^\circ$, $b = 100^\circ/\text{s}$ and $k_v = 0.002\text{Nm}/(\text{rad}/\text{s})$

Figure 3: Simulated saccade response for different model parameters. The left subplot represents the simulated generalized coordinates; the middle the coordinate speeds; right the estimated **EOMs** activations.

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