A muscle-reflex model that encodes principles of legged mechanics, produces human walking dynamics and muscle activities

Conference: IEEE Transactions on Neural Systems and Rehabilitation Engineering, June 2010
Authors: H. Geyer and H. Herr

Jhon Charaja[1] and Luca Borgonovi[1]

[1]Universidade de São Paulo, Brasil

September 15, 2021

Table of Contents

Motivation

The bipedal spring-mass model could describes the legged locomotion dynamics[1]

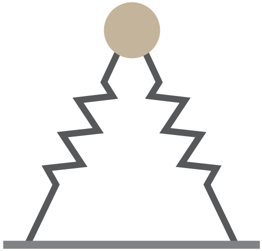


Figure: Spring-loaded inverted pendulum (SLIP)

- SLIP model describes the dynamics during walking and running[1]
- SLIP model is based on self-stability and compliant leg behavior principles[2]
- SLIP model does not present a clear relation with human motor control[2]
- Spinal reflexes can relate sensory information of leg with muscle activation[2]

[1] H. Geyer (2006).

[2] H. Geyer (2010).

Motivation

The bipedal spring-mass model could describes the legged locomotion dynamics[1]

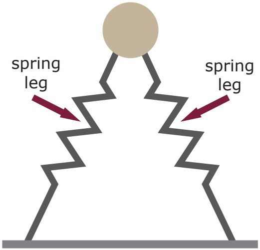


Figure: Spring-loaded inverted pendulum (SLIP)

- SLIP model describes the dynamics during walking and running[1]
- SLIP model is based on self-stability and compliant leg behavior principles[2]
- SLIP model does not present a clear relation with human motor control[2]
- Spinal reflexes can relate sensory information of leg with muscle activation[2]

[1] H. Geyer (2006).

[2] H. Geyer (2010).

Motivation

The bipedal spring-mass model could describes the legged locomotion dynamics[1]

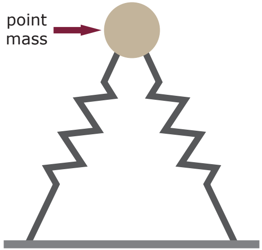


Figure: Spring-loaded inverted pendulum (SLIP)

- SLIP model describes the dynamics during walking and running[1]
- SLIP model is based on self-stability and compliant leg behavior principles[2]
- SLIP model does not present a clear relation with human motor control[2]
- Spinal reflexes can relate sensory information of leg with muscle activation[2]

[1] H. Geyer (2006).
[2] H. Geyer (2010).

Motivation

The bipedal spring-mass model could describes the legged locomotion dynamics[1]

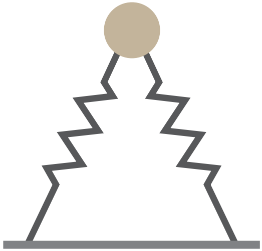


Figure: Spring-loaded inverted pendulum (SLIP)

- SLIP model describes the dynamics during walking and running[1]
- SLIP model is based on self-stability and compliant leg behavior principles[2]
- SLIP model does not present a clear relation with human motor control[2]
- Spinal reflexes can relate sensory information of leg with muscle activation[2]

[1] H. Geyer (2006).
[2] H. Geyer (2010).

Table of Contents

Objective

To develop a neuromuscular human model that encodes the principles of legged locomotion with muscular reflexes

Table of Contents

Table of Contents

New model of human lower limb

- Replacing the spring leg with a segmented leg

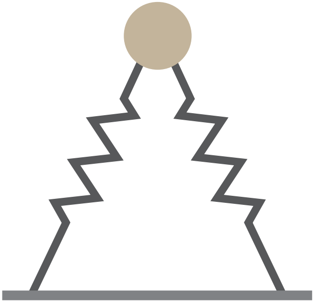


Figure: Spring-loaded inverted pendulum (SLIP)

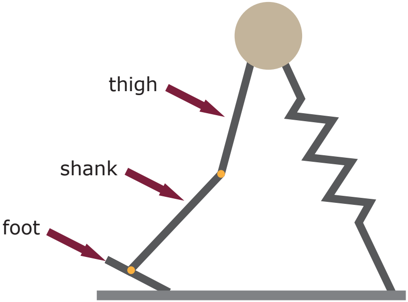


Figure: New model with three segment leg

New model of human lower limb

- Replacing the point of mass with a trunk

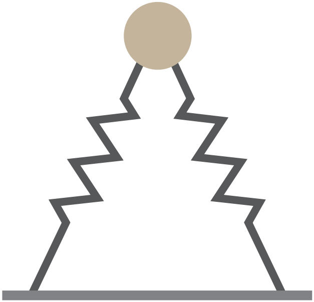


Figure: Spring-loaded inverted pendulum (SLIP)

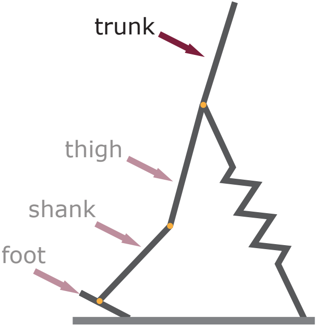


Figure: New model with three segment leg and a trunk

New model of human lower limb

- Vastus group muscle (VAS) generates knee extension motion
- Soleus muscle (SOL) generates ankle plantarflexion motion

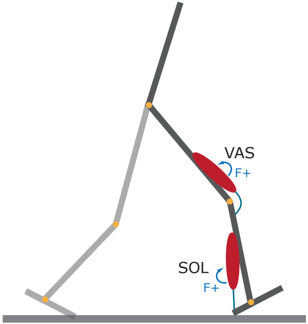
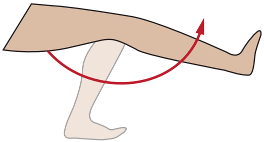
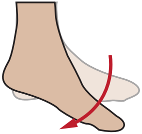


Figure: New bipedal locomotion model with muscles



(a) Knee extension



(b) Ankle dorsiflexion

New model of human lower limb

- Vastus group muscle (VAS) generates knee extension motion
- Soleus muscle (SOL) generates ankle plantarflexion motion

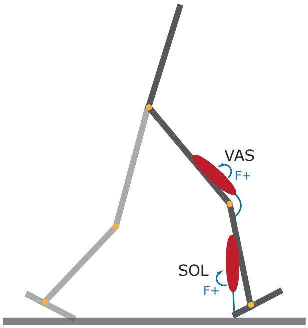


Figure: New bipedal locomotion model with muscles

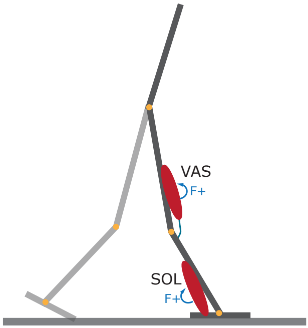


Figure: overextension case

New model of human lower limb

- Gastrocnemius muscle (GAS) generates knee flexion and ankle plantarflexion motion
- Soleus muscle (TA) generates ankle dorsiflexion motion

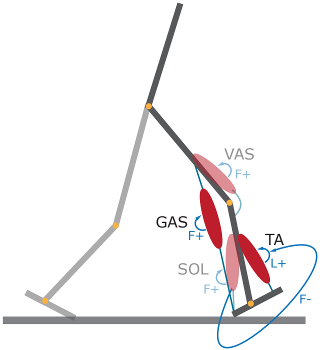


Figure: New bipedal locomotion model with muscles

- GAS prevents knee overextension
- GAS contributes to generate compliant behavior
- TA prevents ankle overextension

New model of human lower limb

- Gluteus muscle group (GLU) generates negative orientation
- Hip flexor muscle group (HFL) generate positive orientation

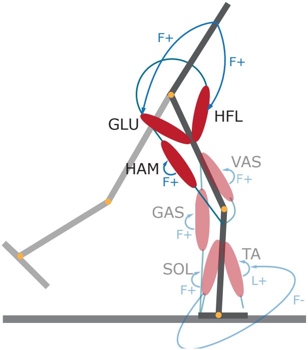


Figure: New bipedal locomotion model with muscles

- GLU and HFL maintain the balance of the trunk
- Hamstring muscle group (HAM) prevents knee hyperextension

Table of Contents

General equation of muscle stimuli

- Spinal reflexes activate muscles during locomotion

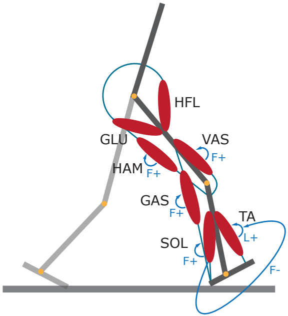


Figure: New bipedal locomotion model with muscles

The stimulation of a muscle is given by

$$S_m(t) = S_{0,m} + G_m F_m \delta t_m,$$
$$\delta t_m = (t - \Delta t_m),$$

where,

- S_m: stimulation
- S_0: prestimulation
- F_m: force
- G_m: gain
- Δt_m: muscle time delay
- ΔL_m: muscle stretch

Table of Contents

Stance phase: initial contact

- Vastus group muscle (VAS) generates knee extension motion
- Soleus muscle (SOL) generates ankle plantarflexion motion

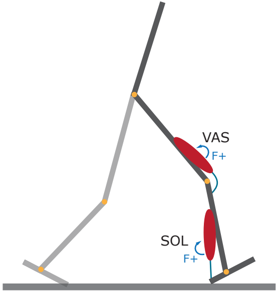


Figure: New bipedal locomotion model with muscles

The stimulation of **VAS** is given by

$$S_{VAS}(t) = S_{0,VAS} + G_{VAS} F_{VAS}(t - \Delta t_{VAS})$$

The stimulation of **SOL** is given by

$$S_{SOL}(t) = S_{0,SOL} + G_{SOL} F_{SOL}(t - \Delta t_{SOL})$$

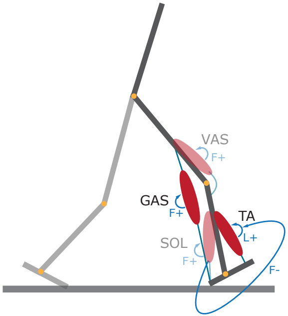
Stance phase: initial contact

The stimulation of **GAS** is given by

$$S_{GAS}(t) = S_{0,GAS} + G_{GAS}F_{GAS}(t - \Delta t_{GAS})$$

The stimulation of **TA** is given by

$$S_{TA}(t) = S_{0,TA} + G_{TA}(\Delta L_{TA})(t - \Delta t_{TA}) - G_{SOL,TA}F_{SOL}(t - \Delta t_{SOL})$$



- GAS prevents knee overextension
- GAS contributes to generate compliant behavior
- TA prevents ankle overextension

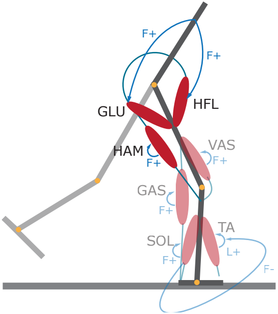
Stance phase: loading response

The stimulation of **GLU** and **HFL** is given by

$$S_{GLU}(t) \sim \pm k_p(\theta - \theta_{ref}) + k_d\dot{\theta}$$

The stimulation of **HAM** is given by

$$S_{HAM} \sim S_{GLU}$$



- GLU generates negative orientation
- HAM prevents knee hyperextension
- HFL generate positive orientation

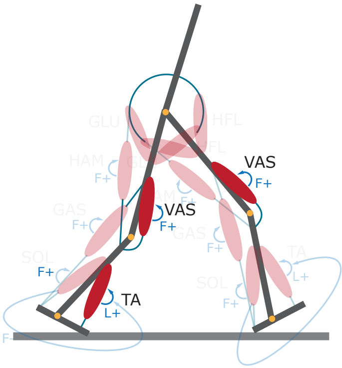
Table of Contents

Swing phase: pre-swing

The VAS of swing leg should be inhibit to allow compliance behavior

The new stimulation of **VAS** is given by

$$S_{VAS}(t) = S_{0,VAS} + G_{VAS} F_{VAS}(t - \Delta t_{VAS}) - k_{bw} |F_{\text{leg}}^{\text{ctr}}|$$



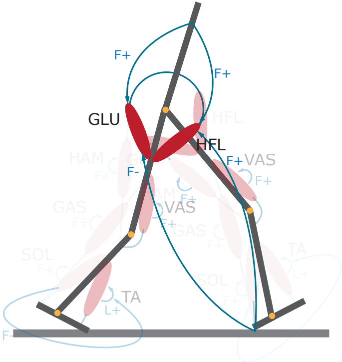
where,

- k_{bw}: gain proportional to body weight
- $F_{\text{leg}}^{\text{ctr}}$: force applied on contralateral leg

Swing phase: pre-swing

The model initiate swing incresing HFL and decresing GLU stimulation

$$S_{HFL}(t) = k_p(\theta - \theta_{ref}) + k_d\dot{\theta} + \Delta S,$$
$$S_{GLU}(t) = k_p(\theta - \theta_{ref}) + k_d\dot{\theta} - \Delta S$$



where,

- ΔS: constant parameter

Table of Contents

Introduction

Hi guys, the title of the article is " " was presented in the conference " " in 2010 by the authors " " .

Motivation

The bipedal spring-mass model is a well-know model that can describe the locomotion dynamics of legged mechanisms.

A

dd support files of spinal reflexes