ugr Universidad de Granada

Fachhochschule Münster University of Applied Sciences

MÜNSTER UNIVERSITY OF APPLIED SCIENCES
Department of Electrical Engineering and Computer Science

Bachelor Thesis

KALMAN FILTERING APPLIED TO ORIENTATION ESTIMATION IN GAIT ANALYSIS

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A thesis submitted in partial fulfilment of the requirements for the degree of Bachelor of Science in Electrical Engineering

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Statement of Authorship

I hereby certify that this bachelor thesis has been composed by myself, and describes my own work, unless otherwise acknowledged in the text. All references and verbatim extracts have been quoted, and all sources of information have been specifically acknowledged. It has not been accepted in any previous application for a degree.

Granada, 26th February 2015

Robin Weiß

Preface

This thesis was submitted in partial fulfilment of the requirements for the degree of Bachelor of Science in Electrical Engineering. It describes the implementation of a new Kalman filter based orientation algorithm to improve the estimation of the orientation angels obtained with a system called GaitWatch that is used for stance and gait analysis by means of inertial sensors.

I took part in the joint research project "Analysis of anticipatory postural adjustments of Parkinson's patients using inertial sensors" between the Research Centre for Information and Communications Technologies of the University of Granada (CITIC-UGR) and the Department of Neurology of the Klinikum Großhadern in Munich, which is part of the Ludwig-Maximilians University. The goal of this project was to carry out an analysis of the so called anticipatory postural adjustments, which are the movements by a human subject between the moment he initiates gait and the first step. The medical community is interested in this procedure, as it can assist the diagnosis of neurodegenerative diseases such as Parkinson's. Prior to this thesis I completed a three-months internship at the CITIC-UGR in which I worked on the synchronisation of a force measuring plate and the GaitWatch system within the above-mentioned project.

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ABSTRACT

Implementation of a new Kalman filter based orientation algorithm

by Robin Weiß

This thesis was submitted in partial fulfilment of the requirements for the degree of Bachelor of Science in Electrical Engineering. It describes the implementation of a new Kalman filter based orientation algorithm to improve the estimation of the orientation angels obtained with a system called GaitWatch that is used for stance and gait analysis by means of inertial sensors.

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Abbreviations

CITIC-UGR	Research Centre for Information and Communications Technologies of the University of Granada

Notation

$\mathcal{S}$ A set

Chapter 1

Introduction

1.1 General

1.2 Goals

1.3 Motivation

1.4 GaitWatch

This paragraph will describe the hardware we used..

The GaitWatch device [?] is a MIMU designed to monitor the motion of patients while attached to the body. It was developed at the Department of Neurology of the Ludwig-Maximilians University in Munich in conjunction with the Department of Signal Theory, Telematics and Communications of the University of Granada. The system is composed of a set of embedded magnetic and inertial sensors wired to a box containing a microcontroller. This microcontroller is in charge of collecting data from the embedded box sensors, as well as from the external measurement units, and storing them on a memory card. The various units are placed at the patient's thighs, shanks, arms and trunk as shown in Figure **??**. The components of the three different kinds of subunits are described below:

- Type A – thighs and shanks:

IMU Analog Combo Board with 5 Degrees of Freedom [1] containing an IDG500 biaxial gyroscope (from which only Y axis is actually used) with a measurement range of ±500°/s [2] and a ±3g triaxial accelerometer, ADXL335 [3].

- Type B – arms:

  IDG500 biaxial gyroscope with a measurement range of ±500°/s [2].

- Type C – trunk:

  ADXL345 triaxial accelerometer with programmable range (±2g/±4g/±8g/±16g) [4], IMU3000 triaxial gyroscope with programmable range (±250/±500/±1000/±3000°/s) [5], Micromag3 triaxial magnetometer with a measurement range of ±11Gauss [6], AL-XAVRB board containing an AVR ATxmega processor [7].

1.5 Methodology

The team in which I was integrated worked using the agile software development methodology. Working software was delivered frequently and was the principal measure of progression. Our self-organising team consisted of three members meeting regularly. Parts of the software were developed doing pair programming. To follow the progress of other team members at any time we used Pivotal Tracker, a tool for agile project management and GitHub, a repository hosting service based on the distributed version control system Git. I used the document markup language LaTeX to write this report.

1.6 Document Structure

Next, in Chapter 2, we will elaborate on the hardware we used and describe the synchronisation process in detail.

Chapter 2

State of the Art

Chapter 3

Fundamentals

3.1 Inertial Sensors

Devices that use a combination of inertial sensors like accelerometers and gyroscopes are referred to as inertial measurement units (IMUs). If they also include magnetic field sensors (magnetometers), they are called magnetic inertial measurement units (MIMUs)Magnetic Inertial Measurement Unit. With these devices the orientation of the body can be obtained with up to nine degrees of freedom, provided that triaxial accelerometers, gyroscopes and magnetometers are used, respectively [**?**].

3.1.1 Accelerometer

3.1.2 Gyroscopes

3.1.3 Magnetometer

3.2 Kalman Filter

3.3 Orientation Estimation

Chapter 4

Implementation

4.1 Realisation in Matlab

Chapter 5

Results and Discussion

5.1 Results

5.2 Discussion

Chapter 6

Conclusion and Future Work

6.1 Conclusions

Summarising the above, I can say that I have learned a lot in the four month that I spent in Granada. Amongst others I have come to know many new work methods, not only due to being exposed to people from a different culture, but also due to the fact that scientific research differs strongly from the work as a student at university. I gained a deeper understanding of Parkinson's disease and how various gait analysis techniques are used to quantify its effects. Therefore I had to study the principles of force plates and inertial measurement units as well as the basics of classification. I was able to improve my MATLAB® skills and have realised how important it is to write understandable and well commented code, if it is for a larger project and not only for a coursework. I am now familiar with tools such as GitHub and Pivotal Tracker which make working in a team much easier and significantly more efficient. Beside my work at the research centre, where I obtained a valuable insight into scientific research, I read a book about scientific writing that helped me to improve my oral and written English skills during my stay. Furthermore I now know the fundamentals of LaTeX.

The above will hopefully serve as a good foundation for my subsequent bachelor's thesis. All in all it was a great experience, professionally as well as personally. I truly recommend such a stay to every university student.

6.2 Future Work

Biomedical research is a very interesting blend of both my major interests, that is, working in the medical field as a paramedic and in the technical field as an electrical engineer. I would like to keep working in this field and write my aforementioned bachelor's thesis here in Granada. There is a variety of possible future work. One related topic would be the validation of the pitch angles measured with the gyroscopes of the GaitWatch by means of cameras that record the trace of visual markers. From these markers one could compute the pitch angels and compare them to the those of the GaitWatch.

A set $\mathcal{S}$

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