

THÈSE

Pour obtenir le grade de

DOCTEUR DE L'UNIVERSITÉ GRENOBLE ALPES

Spécialité : **Informatique**

Arrêtée ministériel : 25 mai 2016

Présentée par

David PAGNON

Thèse dirigée par **Lionel REVERET**
et codirigée par **Mathieu DOMALAIN**

préparée au sein du **Laboratoire Jean Kuntzmann**
dans **l'École Doctorale l'École Doctorale Mathématiques, Sciences et**
technologies de l'Information, Informatique

"Design, evaluation, and application of a workflow for biomechanically consistent markerless kinematics in sports"

"Conception, évaluation, et application d'une méthode biomécaniquement cohérente de cinématique sans marqueurs en sport"

Thèse soutenue publiquement le "**Date de soutenance**",
devant le jury composé de :

Président

Laboratoire, Président

Rapporteur

Laboratoire, Rapporteur

Examinateur

Laboratoire, Examinateur

Lionel REVERET

INRIA Grenoble, Directeur de thèse

Mathieu DOMALAIN

Institut Pprime, Co-Encadrant de thèse

Invité

Laboratoire, Invité



"To all of you who care about more important stuff than what follows."

Acknowledgements

*S*hould I start this by declaring that these PhD years have been alternatively depressing and engaging, exhausting and stimulating, infuriating and enthralling? This is trite, and true for everyone, PhD student or not. Covid pandemic or not. Child birth or not. Struggles in close friends' and relatives' lifes or not. But there it is. Now that it is stated, let me go straight to my acknowledgements.

Above anyone else, I want to thank my mother. She not only had to deal with the difficult task of raising me and putting up with my constant flow of questions, but also with welcoming the four smaller sisters that came after me. As a widow. With debts to pay off, and very little money coming in. Moving every two years, until we settled in for a small appartement in a neighborhood that some would call a ghetto, although we prefered calling it home. And yet, there was always food on the table. Even better, we had no idea how poor we were, because she literally sacrificed her life for ours, and her passions for our interests. This is quintessential Christlike love. We all had the incredible opportunity of doing at least one physical, and one artistic activity, on top of pursuing university level studies. We also learned how to live happily with very little, which I'm starting to realize is a sort of superpower. Most importantly, she made children that all love each other. Now that I'm a father too, I can measure how high she set the bar, and I can only hope to be half as good as her. I can't award her the Legion of Honor she deserves, but at least here is a little bit of recognition! Thank you from all of us, maman.

I also have a deep thought for my father, who tragically passed away when I was still a little child. He did have to struggle with some issues that would eventually cause his death, but I believe he fought until the very end. He is actually the one who taught me a nice lesson of persistence, surely without even trying. A friend and I were racing up a hill, while my father timed us. I lost. We raced again, I lost again. I tried more, and sure enough, I lost every single race. I went to my dad and complained: "I'm tired papa, can we stop?" "Are you tired, really? Very good, it means that you're on your way to make progress!" I paused, and let it sink in for a few moments. And without a word, I went back running. That's how I learned that getting better goes with accepting to suffer a little. Later on, I also realized that out of any bad experience, be it death, you can take away something positive, something that will help you grow. Against all odds, I even made a first professional carrier in sports. I am very grateful for both my parents: I am who I am, with all my quirks and all that's to be loved or to be hated, thanks to them.

So many more people to thank! I'm just getting started, sorry to inflict you this. But let's start with the sisters. Esther comes just after me, she married an awesome guy from Congo, and is currently raising two wonderful little girls. She is the closest to what my mom was with us (and still is), making anyone feel home at any time, always on the move, taking care of her family during the day and working at nights, juggling countless tasks and thinking it is all just natural. Then comes Déborah, although she didn't come alone since Joëlla followed 10 minutes later. But believe it or not, she is slightly more than a twin. She has a high sense of justice and a desire to be helpful, which made her switch from the arts history field to the health one, so as to be more true to herself. Joëlla also is incredible. She fights every day her health issues, could not finish high school but still managed to get a bachelor degree, and she now is a professionnal violinist, whose empathy perspires through all her plays. I'm on a roll now, and I don't think you'll be suprised if I tell you that my last sister, Noémie, is decent enough. She also became a professionnal violinist, she runs every day, and she is currently studying psychology. She also spends a lot of energy mediating arguments between people she loves. A family I'm proud of, not only because of their obvisous skills, but because of their virtues.

I want to thank my grand-parents, whose house was the ground base for all of my aunts, uncles, and cousins, who met there during each and every vacation. They made us discover the delightful joy of being cold, wet and exhausted during rainy hikes, to finally end up above a splendid sea of

cloud from which protruded just a few sharp peaks, over which Alpine choughs maneuvered with their vigorous flight. They are the true pillars of our extended family. The cycle of life being what it is, they became older and can't hike anymore. I am now very happy to see the whole family striving to take care of them, as much as they have been taken care of. I can sadly not name every single other member of my family, humans or animals, but they are all a crucial part of myself.

I do need to spend some time for the love of my life, Mikaela. We met in Lebanon, she is American, she cares about France as little as I care about the USA, and yet she accepted to come here for me, in the armpit of the old and stinky world. She had the courage to take over my mother's difficult job to bear with my incessant questions. She actually has a lot of answers, since the extend of her knowledge is so wide and well-rounded. She is also an awesome writer, and a qualified editor who plays a large role in making my productions publishable. She is much more than she believes of herself: exceedingly faithful, remarkably generous, paradoxically very introverted but willing to help all the persons in need we come across, and unfortunately suffering of how little her power is to make the world a better place. She also comes with a very nice family in law, and of course, she is the mother of my child Cédric! A stunning baby who spends an excessive amount of energy smiling at every one, all day long (aside from sometimes, when he screams his head off.) He might give me a hard time whenever I get started writing my thesis, but he does it in a very cute way. And he always embodies a very good way for us to get away with our shared legendary absent-mindedness. I'm looking forward to the time I'll be old enough for him to change my diapers.

Life wouldn't be life without friends, old and new ones, whether I see them several times a week or once every two or three blue moons. Friends of the family, friends from church, friends from parkour, friends from the performing world, friends I have no idea how I got to know them. Not to brag, but they are too numerous to name them all.

Finally, let's remember that this is a PhD thesis that I'm writing, and that there is no thesis without a lab, without supervisors, without fellow PhD students, post-docs, interns, researchers, administrative workers, cleaning operatives, and all who are involved in making work enjoyable (sic.) I want to thank them all. Lionel, my director, who saved me from the happy hell of starving performing arts to give me the chance to throw myself in another highly precariously fun situation. Mathieu, my co-supervisor, who was quite present and helpful, always ready to give me quick and valuable feedback, despite he lived in the other end of the country. One expert in computer vision, the other in biomechanics: the perfect fit for the objectives of my doctorate. Thibault, my faithful office colleague, that I often left alone with the sole presence of cold-blooded computer hardware while I worked remotely. Other colleagues from other places such as the INSEP, the LBMC, the Pprime institute, etc. Thank you all!

To sum it up, I owe this work to my family, my friends, my colleagues, and I'm guillible enough to believe I owe it to God above all. I am happy I have overcome it, not only alone but with all of the aforenamed people!

On these words, I suppose I can now start with what I'm here for.

Abstract

*A*bstract.

Titre, Abstract, Mots clés

Potentiellement une seule section pour Abstract / Résumé, potentiellement en 2 colonnes (cf template Rennes)

Résumé

Résumé.

Contents

Acknowledgements	i
Abstract	iv
Résumé (en français)	v
Table of contents	vii
General introduction	1
1 State of the art	3
1.1 Overall context of kinematics in sports	4
1.1.1 General context	4
1.1.2 Marker-based systems	4
1.1.3 IMU and RGB-D systems	5
1.1.4 Markerless systems	6
1.2 2D markerless analysis	7
1.2.1 2D pose estimation	7
1.2.2 2D kinematics from 2D pose estimation	7
1.3 3D markerless analysis	8
1.3.1 3D pose estimation	8
1.3.2 3D kinematics from 3D pose estimation	10
1.4 Statement of need	11
2 Theoretical framework	14
2.1 Pose detection	15
2.1.1 Why machine learning?	15
2.1.2 Machine learning timeline and principles	15
2.1.3 Pose detection	19
2.2 3D reconstruction	19
2.2.1 Pinhole camera model	19
2.2.2 Calibration	19
2.2.3 Triangulation	19
2.3 3D joint kinematics	19
2.3.1 Physically consistent model	19
2.3.2 Scaling	20
2.3.3 Inverse kinematics	20
3 Proposed solution: Pose2Sim Python package	22
3.1 Introduction to the workflow	23
3.2 2D pose detection	24
3.3 Pose2Sim core	24
3.3.1 Tracking of the person viewed by the most cameras	24
3.3.2 Triangulating by weighted direct linear transform	24

Table of contents

3.3.3 Filtering	24
3.4 Pose2Sim skeletal model	24
3.5 Limitations and perspectives	24
3.6 Helper functions and vizualisation tools	25
4 Robustness assessment	27
4.1 Introduction	28
4.1.1 Robustness definition	28
4.1.2 Assessing robustness	28
4.2 Methods	28
4.2.1 Experimental setup	28
4.2.2 Participant and protocol	28
4.2.3 Challenging robustness	28
4.2.4 Statistical analysis	29
4.3 Results	29
4.3.1 Data collection and 2D pose estimation	29
4.3.2 Pose2Sim tracking, triangulation, and filtering	29
4.3.3 Relevance, repeatability and robustness of angles Results	29
4.4 Discussion	30
4.4.1 Pose2Sim	30
4.4.2 Relevance, repeatability and robustness	30
4.4.3 Limits and perspectives	30
5 Accuracy assessment	32
5.1 Introduction	33
5.1.1 State of the art	33
5.1.2 Assessing accuracy	33
5.2 Methods	33
5.2.1 Data collection	33
5.2.2 Markerless analysis	33
5.2.3 Marker-based analysis	33
5.2.4 Statistical analysis	34
5.3 Results	34
5.3.1 Concurrent validation	34
5.3.2 Comparison with other systems	34
5.4 Discussion	34
5.4.1 Strengths of Pose2Sim and of markerless kinematic	34
5.4.2 Limits and perspectives	35
5.5 Conclusions	35
6 Application to boxing, using action cameras	37
6.1 Objectives	38
6.1.1 Key Performance Indicators in boxing	38
6.1.2 Limits of research-grade systems in competitions	38
6.1.3 Objectives	38
6.2 Methods	38
6.2.1 4 conditions	38
6.2.2 Pose-calibration on ring dimensions	38
6.2.3 Post-synchronization on 2D movement speeds	39
6.2.4 GoPro spatio-temporal base into Qualysis'	39
6.2.5 Statistical analysis	39
6.3 Results	39

6.4	Discussion	39
6.4.1	Equipment and protocol vs. pose estimation model	39
6.4.2	Pros and cons of different systems	40
7	Application to BMX racing, capturing jointly pilot and bike	42
7.1	Introduction	43
7.1.1	The start in BMX racing	43
7.2	Methods	43
7.2.1	Material and protocol	43
7.2.2	Pilot inverse kinematics	43
7.2.3	Bike inverse kinematics	43
7.2.4	Joined pilot and bike inverse kinematics	43
7.3	Results	44
7.4	Discussion	44
7.4.1	On these data	44
7.4.2	Limits and perspectives	44
General conclusion		46
Bibliography		I
List of figures		XI
List of tables		XIII
A	Appendix A : Title	XV
A.1	Section 1	XVI
A.1.1	Sous section 1	XVI
A.1.2	Sous section 2	XVI
B	Appendix B : Title	XVII
B.1	Section 1	XVIII
B.1.1	Sous section 1	XVIII
B.1.2	Sous section 2	XVIII
C	Appendix C : Title	XIX
C.1	Section 1	XX
C.1.1	Sous section 1	XX
C.1.2	Sous section 2	XX

General introduction

*G*eneral introduction.
Intérêt markerless dans le sport
Présentation du plan

1

State of the art

Motion capture (MoCap) in sports is traditionally performed with marker-based (opto-electronic) systems. However, this presents some drawbacks. As a consequence, alternatives are being investigated, among which thoses offered by Inertial Measurement Units (IMUs) or dept-field (RGB-D) cameras. Markerless analysis from videos sources represents one of the most promising prospects, which has been possible thanks to progress in machine learning. From 2D pose estimation to 3D joint angle determination, this is a new field which opens up new possiblities for motion analysis in a sports context.

This chapter is an up-to-dat and more detailed version of the introduction of the previously published paper "Pose2Sim: An End-to-End Workflow for 3D Markerless Sports Kinematics—Part 1: Robustness" [Pagnon2021]

Contents

1.1	Overall context of kinematics in sports	4
1.1.1	General context	4
1.1.2	Marker-based systems	4
1.1.3	IMU and RGB-D systems	5
1.1.4	Markerless systems	6
1.2	2D markerless analysis	7
1.2.1	2D pose estimation	7
1.2.2	2D kinematics from 2D pose estimation	7
1.3	3D markerless analysis	8
1.3.1	3D pose estimation	8
1.3.2	3D kinematics from 3D pose estimation	10
1.4	Statement of need	11

1.1 Overall context of kinematics in sports

1.1.1 General context

As coaching athletes implies observing and understanding their movements, motion capture (MoCap) is essential in sports. It helps improving movement efficiency, preventing injuries, or predicting performances. For the last few decades, marker-based systems have been considered the best choice for the analysis of human movement, when regarding the trade-off between ease of use and accuracy. However, these methods have proven to be much more challenging in a sports context than in a laboratory setting, and to be generally inappropriate [Mündermann2006, Colyer2018]. As a consequence, other methods have been investigated (see Table ??).

1.1.2 Marker-based systems

Marker-based systems use a network of opto-electronic cameras. Each of these cameras are surrounded by a crown of infrared LEDs, which projects light toward the subject, who is equipped with reflective markers. Ideally, only the light reflected from these markers is captured by the cameras. The camera usually pre-processes the image to make it binary, and only outputs the coordinates of the detected marker (Figure 1.1a).



(a) An opto-electronic camera is traditionnaly surrounded by a crown of infrared LEDs, projecting light toward the subject. The subject wears markers, which reflect light back to the camera. Marker positions are then known in the camera plane.



(b) Once calibrated, a network of these cameras allows for 3D reconstruction of marker positions. Marker coordinates are then used to infer the posture of the subject.

Figure 1.1: Principles of marker-based motion capture. (Figure 1.1a) presents the functioning of an opto-electronic camera. (Figure 1.1b) shows how a network of calibrated motion capture cameras helps obtaining joint angles.

If calibrated, using a network of these cameras allows for triangulating the 2D coordinates. Calibration involves knowing the cameras' intrinsic properties (such as focal length, optical center, distortion) as well as their extrinsic properties (their position and orientation as regards to the global coordinate system.) See Chapter 2.2 on [3D reconstruction](#) for more details. The reconstructed 3D marker positions are then used to optimize the posture of a physically consistent

skeleton, scaled to each individual subject. In particular, this allows for obtaining 3D joint angles at each point in time, commonly referred to as inverse kinematics (IK).

Yet, reflective marker-based camera systems are complex to set up, are time-consuming, and are very expensive. They also require specific lightning conditions, and involve cumbersome cabling. Moreover, markers may fall off the body of the participant due to sharp accelerations or sweat. They can hinder the natural movement of athletes, which is likely to affect their warm-up, focus, and safety. While the accuracy of landmark location is claimed to be sub-millimetric in marker-based methods [Topley2020], marker placement is tedious, intrusive, prone to positioning variability from the operator [Tsushima2003], and subject to skin movement artifacts, especially on soft tissues. Della Croce et al. found out that inter-operator variations in marker placements range from 13 to 25 mm, which can propagate up to 10° in joint angle prediction [Gorton2009, della Croce1999]. For example, tissue artifacts account for up to a 2.5 cm marker displacement at the thigh, which can cause as much as a 3° error in knee joint angles tissues [Benoit2015, Cappozzo1995]. Joint positions must be calculated explicitly in marker-based methods, which introduces more variability: these errors range up to 5 cm, which can contribute up to 3° of error in lower limb joint angles [Leboeuf2019]. Nevertheless, since marker-based methods benefit from decades of research, they are still considered as the reference method for motion capture.

1.1.3 IMU and RGB-D systems

Consequently, other approaches based on alternative technologies have been investigated over the past years. For instance, wearable Inertial Measurement Units (IMUs) can be placed on an athlete's limbs. IMUs are generally made of an accelerometer, a gyroscope, and a magnetometer. The accelerometer measures the linear acceleration, the gyroscope measures the rotational speed, and the magnetometer measures the orientation of the earth magnetic field. Fusing and integrating these signals allows for the determination of their 3D orientations. The orientation of the athlete's limbs can then be used in combination with a skeletal model to infer their posture (Figure 1.2).

IMUs offer the advantages of getting away from all camera-related issues. They are inexpensive, they do not involve any complex setup and calibration, the field of view is larger, they are not sensitive to self- and gear-occlusions, they can be operated outside of a controlled environment, and they can work in real-time [Johnston2019, Chambers2015]. They still have the drawback of being an external equipment to wear, involving high technical skills from the operator, and are sensitive to ferromagnetic disturbances. Above all, they are exposed to drift over time and need to be calibrated every few minutes. Joint angle accuracy is relatively good in the flexion/extension plane, but less so in other rotational planes where errors are greater than 5° for most motions [Zhang2013, Rekant2022]. Moreover, they are not suitable for joint positions assessment, since these are obtained through multiple integrations of the original signal [Ahmad2013].

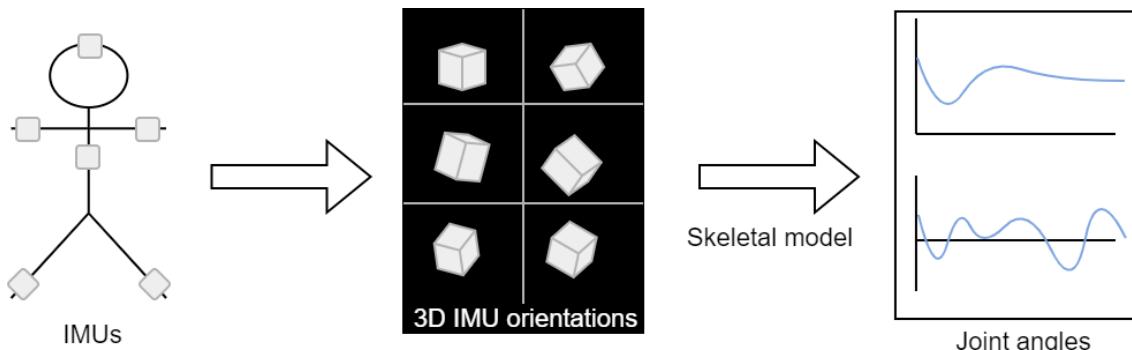


Figure 1.2: IMUs are placed on the subject's limbs. The orientation of the limbs is then used to infer the posture of the subject.

Another approach involves depth-field cameras (RGB-D). Older models projected infrared *structured* light (i.e., a pattern) onto the scene. The relative deformation of the pattern reflected from the scene was then used to estimate depth. Newer models project infrared *modulated* light onto the scene. The time of flight of the light reflected from the scene is then used to estimate depth. Results are commonly considered to be 2.5D, since only the depth of the front facing plane of view is measured. Gait analysis results are natively poor, but after an optimization by a neural network, [Guo2022] manage to get root mean square errors under 7° for knee flexion/extension angle at the most challenging part of the gait cycle, although 3D joint angle errors usually stay under 2-3°. However, it may not perform as well on other motions on which the neural network has not been trained. A network of a few RGB-D cameras can give access to full 3D [Carraro2017, Choppin2013, Colombel2020]. Nevertheless, these cameras hardly function in direct sunlight nor at a distance over 5 meters, and they work at lower framerates (generally under 30 Hz) [Han2013, Pagliari2015].

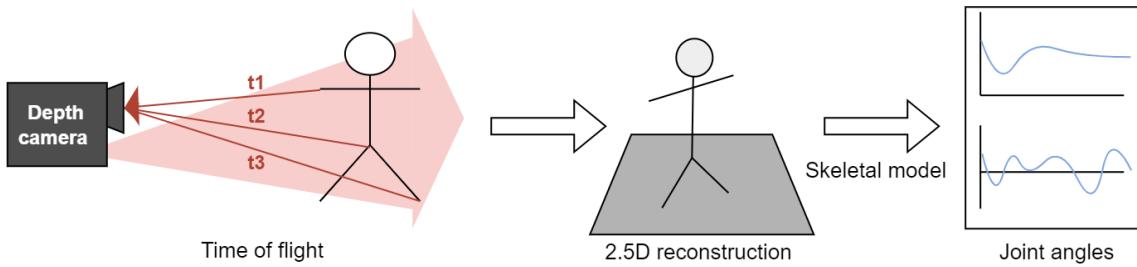


Figure 1.3: A depth-field camera (RGB-D) projects infrared modulated light onto the subject’s body. The time it takes for the light to be reflected to the camera sensor (time of flight) depends on distance, and gives access to the depth of the scene. Older RGB-D cameras use structured light rather than time of flight calculations to infer depth.

1.1.4 Markerless systems

A recent breakthrough has come from computer vision, and the advent of 2D pose estimation from image sources, which quickly became more efficient and accurate. The explosion of deep-learning based methods from camera videos, for which the research has skyrocketed around 2016 [Wang2021], is related to the increase in storage capacities and huge improvements in GPU computing. A search on the ScienceDirect database for “deep learning 3D human pose estimation” produced fewer than 100 papers per year until 2015, and the number is now reaching over 1,000, fitting an exponential curve (Figure 1.4).

It has rekindled interest from the biomechanics community towards image-based motion analysis, which is where it all started with the invention of chronophotography in the 19th century by Marey in France, and Muybridge in the USA [Baker2007]. Currently, two approaches co-exist in human and animal motion analysis: the first one mostly focuses on joint positions, and is lead by the computer vision and the deep-learning communities; while the second one is interested in joint angles, such as the biomechanics community uses to obtain physically coherent kinematics individualized to each subject. One of the main current challenges is to bridge the gap between these two worlds, and to take advantage of deep-learning technologies for kinematic analysis [Cronin2021, Seethapathi2019].

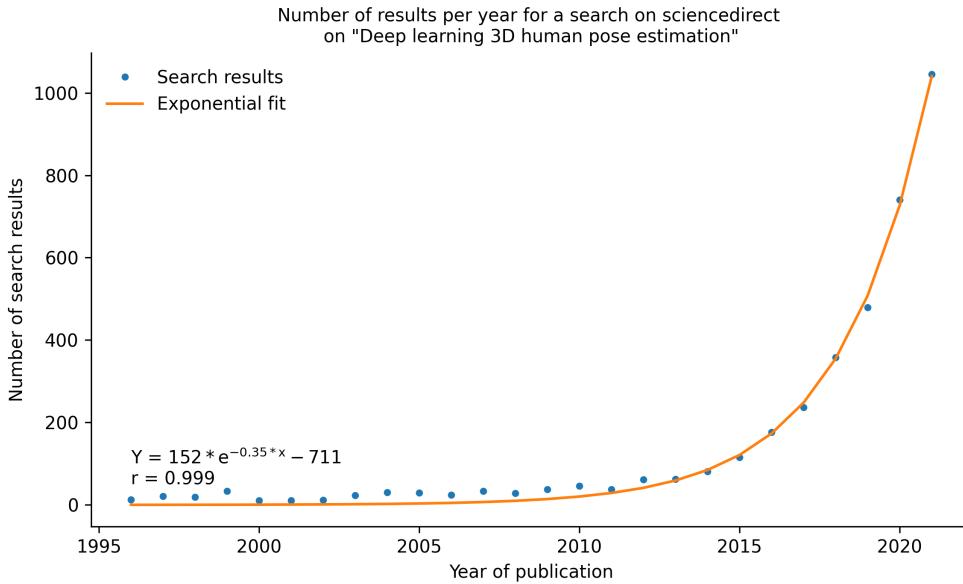


Figure 1.4: The search for “deep learning 3D human pose estimation” (dots) fits an exponential curve (line). The search produced less than 100 results until 2015, and is now well over a 1,000 per year.

1.2 2D markerless analysis

1.2.1 2D pose estimation

The most well-known off-the-shelf 2D human pose estimation solutions are OpenPose [Cao2019] (Figure 1.5), and to a lesser extent AlphaPose [Fang2017]. While both show similar results, OpenPose has the advantage of being a bottom-up approach, whose computation time does not increase with the number of persons detected [Cao2019]. A bottom-up approach first detects all available joint keypoints, and then associates them to the right persons; while a top-bottom approach first detects bounding boxes around each person, and then finds joint keypoints inside of them. OpenPose has been trained on the CMU Panoptic Dataset [Joo2015], with 511 synchronized videos of multiple people in motion, alone or engaged in social activities.

Other approaches have shown even better results on evaluation datasets (see review [Chen2020]), but they are generally slower and not as widespread. The technology, however, is still maturing and some light-weight systems such as BlazePose [Bazarevsky2020] or UULPN [Wang2022] are being proposed, which can operate in real time on a mobile phone; however, they are still not quite as accurate as required for quantitative motion analysis.

Two other 2D pose estimation toolboxes are DeepLabCut [Mathis2018] and SLEAP [Pereira2022], which were initially intended for markerless animal pose estimation. They have the advantage that they can be custom trained for the detection of any human or not human keypoint with a relatively small dataset. All of the tools presented in this section are open-source.

1.2.2 2D kinematics from 2D pose estimation

Some authors bridge 2D pose estimation to more biomechanically inspired variables, such as in gait kinematics analysis. Kidzinski et al. present a toolbox for quantifying gait pathology that runs in a Google Colab [Kidziński2020]. Stenum et al. evaluate gait kinematics calculated from OpenPose input concurrently with a marker-based method. Mean absolute error of hip, knee and ankle sagittal angles were 4.0° , 5.6° and 7.4° [Stenum2021]. Liao et al. have not released their code, but they use OpenPose outputs to train a model invariant to view [Liao2020]. Viswakumar



Figure 1.5: 2D pose estimation by OpenPose. Image courtesy of [Cao2019].

et al. perform direct calculation of the knee angle from an average phone camera processed by OpenPose [Viswakumar2019]. They show that OpenPose is robust to challenging clothing such as large Indian pants, as well as to extreme lightning conditions. Other sports activities have been investigated, such as lower body kinematics of vertical jump [Drazan2021] or underwater running [Cronin2019]. Both works train their own model with DeepLabCut. Serrancoli et al. fuse OpenPose and force sensors to retrieve joint dynamics in a pedaling task [Serrancoli2020]. Although it doesn't specifically use deep-learning approaches, an other noteworthy tool for 2D sports movement analysis is Kinovea [Fernández-González2020]. It allows to manually label keypoints on a frame, and track them in time in order to obtain point trajectories or angle data.

1.3 3D markerless analysis

1.3.1 3D pose estimation

There are a lot of different approaches for markerless 3D human pose estimation, and listing them all is beyond our scope (see review [Wang2021]). Some more ancient ones are not based on deep-learning and require specific lightning and background conditions, such as visual-hull reconstruction [Ceseracciu2014]. Some directly lift 3D from a single 2D camera (see review [Liu2022c]), with different purposes: one estimates the positions of a set of keypoints around the joint instead of determining only the joint center keypoint, so that axial rotation along the limb is solved [Fisch2020]; SMPL and its sequels retrieve not only joint positions and orientations, but also body shape parameters [Loper2015]; while XNect primarily focuses on real time [Mehta2020]. A few approaches even strive to estimate 3D dynamics and contact forces from a 2D video input [Li2019, Rempe2021, Louis2022]. Some incorporate kinematic priors into their neural networks in order to take advantage of human knowledge [Xu2020]. Surprisingly, this does not seem to be done in multi-view approaches. Rempe et al. solve occlusions from a 2D input [Rempe2020], but this remains a probabilistic guess that may be unsuccessful in case of unconventional positions of hidden limbs, whereas using more cameras would have given more trustworthy results.

Some research attempts to solve 3D pose estimation from a network of uncalibrated cameras, i.e., cameras whose extrinsic parameters (translation and rotation with respect to the coordinate system), intrinsic parameters (focal length, pixel size, etc.), and distortion coefficients are not known (See Chapter 2.2 on [3D reconstruction](#) for more details.) It either uses 2D pose estimations of each view as visual cues to calibrate on [Takahashi2018, Xu2021, Liu2022a], or an adversar-

ial network that predicts views of other cameras, compares them to real views, and adjusts its calibration accordingly [Ershadi-Nasab2021]. Dong et al. recover 3D human motion from unsynchronized and uncalibrated videos of a repeatable movement found on internet videos (such as a tennis serve performed by a celebrity) [Dong2020]. Using uncalibrated videos is still a very experimental trend, that would require more research before being used in biomechanics.

We choose to focus on the methods that estimate 3D pose by triangulating 2D pose estimations from a network of multiple calibrated cameras. The classical evaluation metric is the MPJPE (Mean Per Joint Position Error), which is the average Euclidian distance between the estimated joint coordinate and its ground truth. Most methods take OpenPose as an input for triangulation, and more specifically the body_25 model. Labuguen et al. evaluate 3D joint positions of a pop dancer with a simple Direct Linear Transform triangulation (DLT [Hartley1997,Miller1980]) from 4 cameras [Labuguen2020]. Apart from the upper body for which error goes up to almost 700 mm, the average joint position error is about 100 mm. Nakano et al. examine three motor tasks (walking, countermovement jumping, and ball throwing), captured with 5 cameras and triangulated with the same methods, with a subsequent Butterworth filter [Nakano2019]. 47% of the errors are under 20 mm, 80% under 30 mm, and 10% are above 40 mm. The largest errors are mostly caused by OpenPose wrongly tracking a joint, for example by swapping the left and the right limb, that causes large errors up to 700 mm. This may be fixed either by using a better 2D pose estimator, or by using more cameras to reduce the impact of an error on a camera, or else by considering the temporal continuity in movement. Needham et al. use 9 cameras and find that ankle MPJPEs are within the margin of error of marker-based technologies (1–15 mm), whereas knee and hip MPJPEs are greater (30–50 mm). These errors are systematic and likely due to "ground-truth" images being mislabeled in the training dataset [Needham2021]. They also run the comparison with AlphaPose and with DeepLabCut. While AlphaPose's results are similar to OpenPose's; DeepLabCut errors are substantially higher.

Slembrouck at al. go a step further and tackle the issue of limb swapping and of multiple persons detection [Slembrouck2020]. In case of multiple persons detection, one needs to make sure they associate the person detected on one camera to the same person detected on other ones. Slembrouck et al. manage to associate persons across cameras by examining all the available triangulations for the neck and mid-hip joints: the persons are the same when the distance between the triangulated point and the line defined by the detected 2D point and the camera center is below a certain threshold. They only focus on lower limb. Their first trial features a person running while being filmed by seven cameras, whereas their second one involves a person doing stationary movements such as squats while filmed by 3 cameras. After filtering, the average positional error in the first case is about 40 mm, and it is roughly 30 mm in the second case (less than 20 mm for the ankle joint). Other authors deal with the multiperson issue in a slightly different way [Bridgeman2019, Chu2021, Dong2019]. In average, if the detected persons are correctly associated and the limbs don't swap, the average joint position error for an OpenPose triangulation is mostly below 40 mm.

Some triangulation methods not based on OpenPose reach even better results on benchmarks, although it comes at the cost of either requiring heavy computations, or of being out of reach for non-expert in deep-learning and computer vision. The classic approach reduces the joint detection heatmap to its maximum probability, and then to triangulate these scalar 2D positions. Instead of this, the main state-of-the art methods directly perform a volumetric triangulation of the whole heatmaps, and only then take the maximum probability as a 3D joint center estimate. By working this way, they keep all the information available for as long as possible. They manage to lower their MPJPE to about 20 mm [He2020, Iskakov2019].

1.3.2 3D kinematics from 3D pose estimation

Numerous studies have focused on the accuracy of 3D joint center estimation, but far fewer have examined joint angles [Zheng2022]. Yet, when it comes to the biomechanical analysis of human motion, it is often more useful to obtain joint angles. Joint angles allow for better comparison among trials and individuals, and they represent the first step for other analysis such as inverse dynamics. This issue is starting to be tackled. Zago et al. evaluate gait parameters computed by triangulating 2 videos processed by OpenPose, and notice that straight gait direction, longer distance from subject to camera, and higher resolution make a big difference in accuracy [Zago2020]. D’Antonio et al. perform a simple triangulation of the OpenPose output of two cameras, and compute direct flexion-extension angles for the lower limb [D’Antonio2021]. They compare their results to IMU ones, and point out that errors are higher for running than for walking, and are also rather inconsistent: Range of Motion (ROM) errors can reach up to 14°, although they can get down to 2 to 7° if the two cameras are set laterally rather than in the back of the subject. Wade et al. calculate planar hip and knee angles with OpenPose, AlphaPose, and DeepLabCut with the input of 9 cameras [Wade2021]. They deem the method accurate enough for assessing step length and velocity, but not for joint angle analysis. AniPose, a Python open-source framework, broadens the perspective to the kinematics of any human or animal with a DeepLabCut input, instead of OpenPose. They offer custom temporal filters, as well as spatial constraints on limb lengths [Karashchuk2021]. To our knowledge, it has only been concurrently validated for index finger angles in the sagittal plane, resulting in a root-mean-square error of 7.5° [Geelen2021].

The previous studies calculated simple planar angles between 3 joint centers. However, the human skeleton is complex and not only made of pin joints: aside from the flexion/extension rotation axis, the abduction/adduction axis and the internal/external axis are typically also engaged; and some joints also involves some translation, such as the shoulder. In this case, either several markers per joints or a solid skeletal model are needed. So far, little work has been done towards obtaining 3D angles from multiple views [Zheng2022]. Aside from our solution (see Chapter 3 on [Pose2Sim](#)), two main others are worth mentioning. Theia3D is a commercial software application for human gait markerless kinematics. It estimates the positions of a set of keypoints around the joint, and then uses a multi-body optimization approach to solve inverse kinematics [Kanko2021a, Kanko2021b]. They notice an offset in hip and ankle angles between their markerless system and the reference marker-based one, likely due to different skeletal models. Once this offset is removed, the root mean square error (RMSE) in lower limb roughly ranges between 2 and 8° for flexion/extension and abduction/adduction angles, and up to 11.6° for internal/external rotation. Although the GUI is user-friendly, it is neither open-source nor customizable. OpenCap [Uhrlrich2022] has recently been released, and offers a user-friendly web application working with low-cost hardware. It predicts the coordinates of 43 anatomical markers from 20 triangulated keypoints, imports them in OpenSim, and performs classic inverse kinematics with numerous inferred markers and a skeletal model. However, the source code has not yet been released.

Other approaches don’t focus so much on keypoint detections, and capture the whole shape of participants. [Reveret2020] records the 3D shape of a speed climber in a studio equiped with 68 video cameras, and then animates it to follow 2 calibrated drone views by optimizing its manifold parameters. This allows for tracking the center of mass and for detecting hand contacts with holds, without the use of machine learning. Simi shape, a commercial software, jointly learns 2D shape and 2D keypoint coordinates. It claims to be able to obtain accurate kinematics with few cameras, thanks to the additional information shape detection provides (validation with their newer machine learning based process not yet published.) Pose estimation from videos can also be fused with the information provided by other sensors, such as IMUs [Bao2022, Zhang2020]. This enables solving occlusions in videos, and compensation of the drift consecutive to the integration of accelerations and rotation speeds in IMUs. For example, Haralabidis et al. fuse OpenPose results from a single monocular video and two IMU outputs, and solve kinematics of the upper

body in OpenSim (an open-source biomechanical 3D analysis software [[Delp2007](#), [Seth2018](#)]) in order to examine the effects of fatigue on boxing [[Haralabidis2020](#)]. Results are promising, but this cannot be considered as fully markerless. Fusing the depth map of a single RGB-D camera with its image processed by OpenPose has also been investigated [[Liu2022b](#)], although 3D coordinate errors were close to 10 cm.

1.4 Statement of need

According to Atha [[Atha1984](#)], an ideal motion analysis system involves the collection of accurate information, the elimination of interference with natural movement, and the minimization of capture and analysis times. Yet, even though a marker-based system gives relatively accurate results, it requires placing markers on the body, which can hinder natural movement, it is hard to set up outdoors or in context, and it is strenuous to analyse. As a consequence, in the overwhelming majority of cases, coaches solely use subjective visual observation to assess an athlete's movement patterns and to compare performances. As a matter of fact, despite the advantages of technology, investing in it has its pitfalls: the information gathered can be unhelpful, or inaccurate, or not easily interpretable, or simply not implementable in the context of sports [[Windt2020](#)].

The emergence of markerless kinematics opens up new possibilities. Indeed, a network of RGB cameras does not assume any particular environment, and it does not hinder the athlete's movement and focus. However, it still requires delicate calibration, complex setup, large storage space, and high computational capacities. Gathering reliable and usable kinematic data in context is an ambitious challenge, but research has been accelerating in the last few years (Figure 1.4), as have better results.

The objective of this thesis is to participate in building a bridge between the communities of computer vision and biomechanics, by providing a simple and open-source pipeline connecting the two aforementioned state-of-the-art tools: OpenPose and OpenSim. Robustness and accuracy will be assessed, and concrete applications in elite sports context will be discussed.

Sensor type	Mono/Multi camera	2D/3D	Pros and Cons
Opto-electronic	Multi	3D	<ul style="list-style-type: none"> + Standard + Good ease-of-use/accuracy trade-off - Not suitable in sports contexts
IMU	N/A	3D	<ul style="list-style-type: none"> + Good angle accuracy - Angle drift & poor position analysis - Can be cumbersome
Depth	Mono	2.5D	<ul style="list-style-type: none"> + Markerless - Generally poor accuracy - Frame-rate ≤ 30 Hz - Needs distance $\leq 5m$ and no direct sunlight
	Multi	3D	<ul style="list-style-type: none"> + Full 3D markerless + Better accuracy - Same as above re. frame-rate, distance, and light
	Mono	2D	<ul style="list-style-type: none"> + Very robust in all contexts + Cheap and easy to setup - Only 2D - Not very accurate
Video	Multi uncalibrated	3D	<ul style="list-style-type: none"> + Full 3D with one single RGB camera - Probabilistic guess when occlusions: accuracy ↘ - Slow
	Multi calibrated	3D	<ul style="list-style-type: none"> + Removes difficult step of calibration - Still experimental
	Multi calibrated with kin. constraints	3D	<ul style="list-style-type: none"> + Solves occlusions + Robust - Systematic offsets due to labelling errors - Calibration can be challenging
Sensor fusion	N/A	3D	<ul style="list-style-type: none"> + Compensates offsets + Constrains limb lengths and joint angles - Still inaccurate pelvis angles • With IMUs: More accurate, but not markerless • With one RGB-D camera (Depth + OpenPose on RGB): still inaccurate

Tableau 1.1: Pros and cons in state of the art approaches for human motion analysis. The multi-person prospect is not addressed, as it can be available with all approaches, but it is not always. IMU: Inertial Measurement Unit. N/A: Not Applicable. kin.: kinematic. RGB-D: red-green-blue-depth.

2

Theoretical framework

Obtaining kinematics from a network of calibrated video cameras means resolving a few theoretical points. First, features must be recognized in images. This is now mostly done with machine learning models. Then, cameras need to be calibrated, so that all of the 2D features detected for each cameras can be reconstructed in the 3D space. Finally, these coordinates must be constrained to a biomechanically consistent model, in order to obtain coherent joint kinematics.

Contents

2.1	Pose detection	15
2.1.1	Why machine learning?	15
2.1.2	Machine learning timeline and principles	15
2.1.3	Pose detection	19
2.2	3D reconstruction	19
2.2.1	Pinhole camera model	19
2.2.2	Calibration	19
2.2.3	Triangulation	19
2.3	3D joint kinematics	19
2.3.1	Physically consistent model	19
2.3.2	Scaling	20
2.3.3	Inverse kinematics	20

2.1 Pose detection

2.1.1 Why machine learning?

As a first step, achieving motion analysis from a network of cameras involves detecting features in images. These features can be whole human beings, joint centers, body landmarks, sports gear such as tennis balls, climbing holds, or much more.

Two broad approaches can be implemented: the first one consists in using dedicated algorithms for each task. The gist of it is to understand the task well enough to build an appropriate solution. Among other techniques, corner and contour detection, color thresholding, affine transformation, template matching, watershed segmentation, can be used. For example, if one wants to differentiate two boxers wearing respectively a blue and a red shirt, they can filter them by color. If one needs to identify on which portion of a speed climbing wall an athlete is, they can match the template of each holds on the whole image. OpenCV [Bradski2000] provides convenient tools for this purpose, in C++ and Python languages. This approach is often fast, but also quite complicated to implement, and neither flexible nor robust. If there is other red or blue patches in the boxing scene, if the boxer wears green or if the light is poor, this will not work anymore. Likewise for holds, if the sun casts a large shadow which changes its apparent shape, or if holds are seen from a different perspective.

The second approach takes advantage of machine learning algorithms, which constitute an entirely different paradigm. The idea is to show the machine enough examples for it to "understand" by itself its underlying attributes, so that it manages to detect and label automatically new images. This can be used for both aforementioned tasks, in a much more flexible way: if one wants the system to recognize boxers or holds in challenging condition, they simply have to include such examples while training the machine learning model. The machine learning approach is also suitable for other tasks, such as whole-image classification (i.e., determining whether this a boxing or a climbing scene), background extraction [Bouwmans2019], instance segmentation (i.e., extracting the shape of the climber, as well as each holds, the wall, the background, etc.) [Minaee2021], or keypoint detection (e.g., localization of human joint centers in an image [Chen2020]).

2.1.2 Machine learning timeline and principles

Machine learning is a subset of artificial intelligence (AI.) As such, one can trace its origin back to the discovery of the natural neuron at the end of the 19th century, by Nobel Prize Ramón y Cajal [López-Muñoz2006], followed half a century later by the first model of an artificial neuron [McCulloch1943]. A natural neuron is a simple learning unit, which collects the nervous influx sent by other neurons to its dendrites, and sends an action potential when the total influx weighted and summed in the soma overcomes a threshold value. This potential is then transmitted through the axon to the next neuron as a new influx. Similarly, an artificial neuron receives output vectors from previous neurons, weighs and sums them with a summation function, and transfers the resulting output vector to the next neurons if it reaches a certain threshold determined by an activation function (Figure 2.1).

The perceptron, invented in 1956 [Rosenblatt1958], represents the first practical application of an artificial neuron. It acts as a binary classifier which predicts class 1 if the neuron is fired, and class 0 otherwise. It automatically adjusts its weights by learning from example data (see Algorithm 1). It could be used, for example, to predict whether an athlete is going to be "good" or not, given his force-velocity results on an ergometer test (see step-by-step Example 1 and Figure 2.2). Of course, this example is oversimplified. Being good or not as a sport is a complex and multifactorial outcome, and two variables can't sum it up. However, the perceptron can take more than two variables as inputs (for example, force, velocity, and endurance), and it can also be generalized to multiclass classification with more than two outputs (for example, to differentiate between strong, explosive, and resistant type of athletes.)

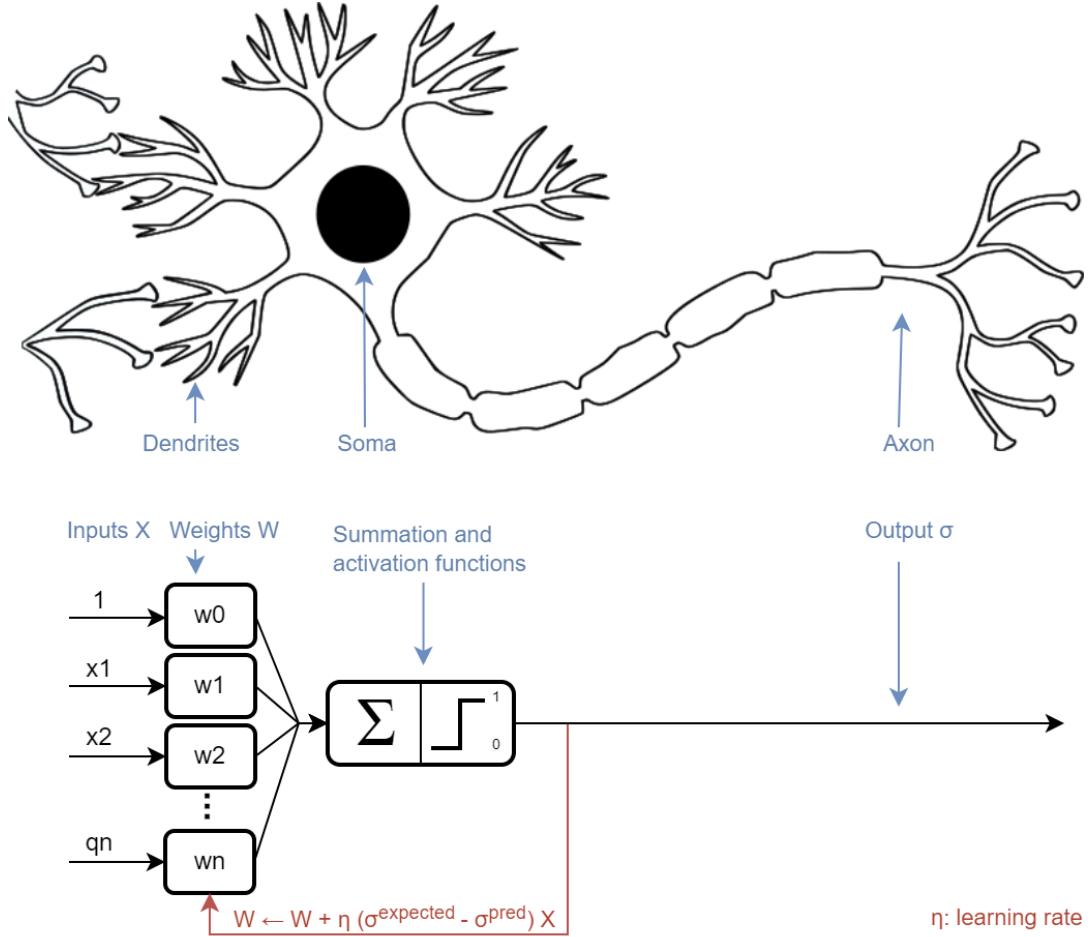


Figure 2.1: The artificial neuron has been modeled after the natural neuron. Inputs and weights act as the total nervous influx firing the dendrites. The collected values are summed, and a signal is activated if a threshold is overcome, as the soma does in a natural neuron. The output signal is conveyed through the axon. In the case of a perceptron classifier, the neuron adjusts its weights to minimize the error between the predicted and the expected output.

Algorithm 1 Perceptron

Let \vec{X}^0 be the input vector of a first instance of variables $(1, x_1^0, \dots, x_m^0)$, \vec{W}^0 the corresponding weights randomly initialized $(w_0^0, w_1^0, \dots, w_m^0)$ with w_0^0 a bias, and $\sigma^{0,pred}$ the output predicted binary class.

1: The summation function is computed:

$$\vec{W}^0 \cdot \vec{X}^0 = \sum_{k \in [0, m]} w_k^0 x_k^0 \quad (2.1)$$

2: This result is processed by an activation function, which is a threshold in the case of the perceptron. It determines whether the neuron will be fired or not, i.e., whether one or the other class will be predicted. $\sigma^{0,pred} = 1$ corresponds to one class, and $\sigma^{0,pred} = 0$ to the other.

$$\sigma^{0,pred} = \begin{cases} 1 & \text{if } \vec{W}^0 \cdot \vec{X}^0 > \theta, \\ 0 & \text{otherwise} \end{cases} \quad (2.2)$$

3: This prediction $\sigma^{0,pred}$ is compared to the actual class $\sigma^{0,expected}$.

$$\varepsilon^0 = \sigma^{0,expected} - \sigma^{0,pred} \quad (2.3)$$

4: Then weights are updated:

$$\vec{W}^1 = \vec{W}^0 + \eta \varepsilon^0 \vec{X}^0 \quad (2.4)$$

with η the learning rate $\in [0,1]$. Note that if the class is correctly predicted, then $\varepsilon^0 = 0$ and weights are not adjusted.

5: The algorithm is repeated with another example \vec{X}^1 , and so on until it has gone through the whole batch of the training set. If weights still need to be updated, one can go over it again, for a determined number of epochs or until the average error is under a given value. Then the perceptron is considered trained, and ready to correctly predict a class σ with the retained weights.

Example 1 Athlete classification with a perceptron

N.B. The code for running this example is available on the thesis repository
https://github.com/davidpagnon/These_David_Pagnon/blob/main/Thesis/Chap2/perceptron.py.

Let's consider force-velocity test results as an input

$$\vec{X} = (1, velocity \text{ (m/s)}, force \text{ (hN)}),$$

and the classification of an athlete as "good" or "bad" as an output $\sigma = 1 \text{ or } 0$.

A batch of training data, i.e., example data the perceptron will learn from, could be:

$$\{(\vec{X}^i, \sigma^{i,expected})\}_{i \in [0,4]} = \{((1,1,5), 1), ((1,2,3), 0), ((1,7,1), 1), ((1,4,1), 0), ((1,5,4), 1) \}$$

Let's randomly initialize weights at $\vec{W}^0 = (-9, 1, 3)$, take a threshold $\theta=0.1$, and a learning rate $\eta = 0.3$.

The first instance of the training set gives:

$$\vec{W}^0 \cdot \vec{X}^0 = \sum_{k \in [0,2]} w_k^0 x_k^0 = -9 \times 1 + 1 \times 1 + 3 \times 5 = 7.$$

Now $\vec{W}^0 \cdot \vec{X}^0 = 7 > \theta = 0.1$, so $\sigma^{0,pred} = 1$.

$\sigma^{0,expected} = 1 = \sigma^{0,pred}$, so the prediction is true and weights don't need to be updated.

As a consequence, $\vec{W}^1 = \vec{W}^0 = (-9, 1, 3)$.

The second instance gives $\vec{W}^1 \cdot \vec{X}^1 = (-9, 1, 3) \cdot (1, 2, 3) = 2 > \theta = 0.1$, so $\sigma^{1,pred} = 1$.

But $\sigma^{1,expected} = 0 \neq \sigma^{1,pred} = 1$, so weights need to be updated.

The error is $\varepsilon^1 = \sigma^{1,expected} - \sigma^{1,pred} = 0 - 1 = -1$.

As a consequence, $\vec{W}^2 = \vec{W}^1 + \eta \varepsilon^1 \vec{X}^1 = (-9, 1, 3) + 0.1 \times (-1) \times (1, 2, 3) = (-9.3, 0.4, 2.1)$.

Third instance: $\vec{W}^2 \cdot \vec{X}^2 = (-9.3, 0.4, 2.1) \cdot (1, 7, 1) = 3 - 4.4 < 0.1$, so $\sigma^{2,pred} = 0$.

$\sigma^{2,expected} = 1 \neq \sigma^{2,pred} = 0$, so weights need to be updated.

$\varepsilon^2 = \sigma^{2,expected} - \sigma^{2,pred} = 1$.

$\vec{W}^3 = \vec{W}^2 + \eta \varepsilon^2 \vec{X}^2 = (-9.3, 0.4, 2.1) + 0.1 \times 1 \times (1, 7, 1) = (-9, 2.5, 2.4)$.

Fourth instance: $\vec{W}^3 \cdot \vec{X}^3 = (-9, 2.5, 2.4) \cdot (1, 4, 1) = 3.4 > 0.1$, so $\sigma^{3,pred} = 1$.

$\sigma^{3,expected} = 0 \neq \sigma^{3,pred} = 1$, so weights need to be updated.

$$\begin{aligned}\varepsilon^3 &= \sigma^{3,expected} - \sigma^{3,pred} = -1. \\ \vec{W}^4 &= \vec{W}^3 + \eta \varepsilon^3 \vec{X}^3 = (-9, 2.5, 2.4) + 0.1 \times (-1) \times (1, 4, 1) = (-9.3, 1.3, 2.1).\end{aligned}$$

Fifth instance: $\vec{W}^4 \cdot \vec{X}^4 = (-9.3, 1.3, 2.1) \cdot (1, 5, 4) = 17.6 > 8$, so $\sigma^{4,pred} = 1$.

$\sigma^{4,expected} = 1 = \sigma^{4,pred} = 1$, so weights don't need to be updated.

$$\vec{W}^5 = \vec{W}^4 = (-9.3, 1.3, 2.1) \text{ (Figure 2.2).}$$

Next instances: Once we have gone over the batch of training data, if the average error is below a given value, we can assume that the perceptron is trained. If not, we can use the next batch to pursue training. If it still didn't converge after all batches, we can iterate over all training data again, for a given number of times. If results are still not satisfying, either the data are not linearly separable, or the training sample is not large enough or of good enough quality. In our case, it seems like our example data have allowed us to correctly separate good and bad athletes based on their force and velocity test results (Figure 2.2).

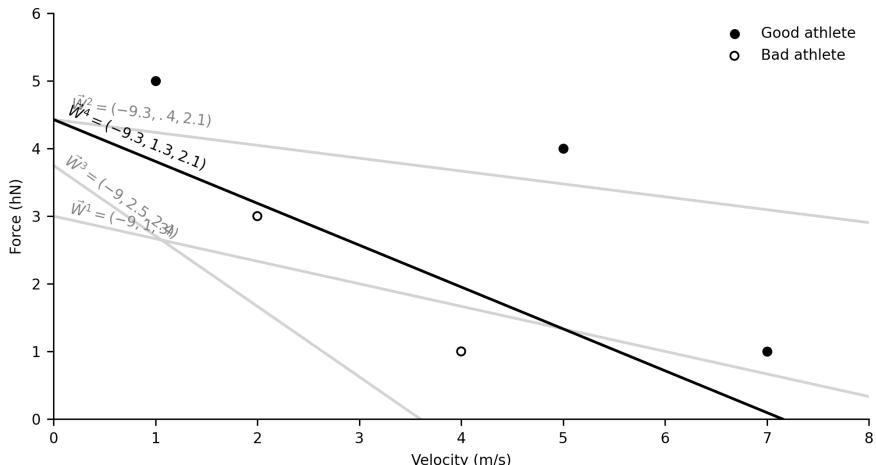


Figure 2.2: Classification of athletes as "good" (black dot) or "bad" (circle) according to their Force-Velocity results. Weights are adjusted (grey lines), until the perceptron classifies athletes correctly (black line.)

Nevertheless, it often takes a lot of iterations over good quality training data for the perceptron to converge. Moreover, it does converge if and only if the data are linearly separable, i.e., if they can be separated with a straight line [Novikoff1963] (see Figure 2.3). Some fundamental problems such as the exclusive OR (XOR) gate can't be solved with a basic single layer ANN [Minsky1969]. This constituted one of the early setbacks for AI. Then, the high computational cost of these approaches, combined with the complexity of common-sense problems, hampered the trust in learning methods. Vision and language problems require enormous amounts of information, and can't be solved with a simple dictionary (for example, "the spirit is willing but the flesh is weak" becomes "the vodka is good but the meat is rotten" when translated back and forth from English to Russian.) Overinflated promises and expectations, followed by disappointment in academia and industries, lead to cuts in fundings, and eventually loss of skills in the 1970s: this is referred to as the first AI winter.

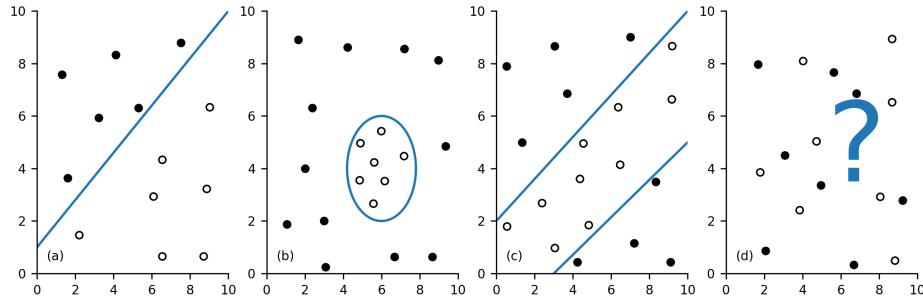


Figure 2.3: Single layer artificial neural networks such as the perceptron can only classify linearly separable data. (a) is linearly separable. (b) is not linearly separable. However, data are contained in an ellipse. The equation of an ellipse is of the form $a \times x^2 + b \times y^2 = 1$, so if we transform the feature variables into $X = x^2$ and $Y = y^2$, the data become linearly separable. (c) is equivalent to a fundamental XOR gate, and is not linearly separable, which was part of the reasons for the first AI winter. It can either be solved by combining several layers of artificial neurons, or by complex kernel tricks which map the data from the original space into a higher dimensional space where they become linearly separable. (d) is not linearly separable. AI: Artificial Intelligence. XOR: Exclusive OR.

2.1.3 Pose detection

Different architectures, different models, different datasets Discriminative vs generative

2.2 3D reconstruction

While some approaches only rely on 2D pose estimation to infer 3D pose with another machine learning model, they are generally not considered to be sufficiently reliable. It is, then, important to use the input from several cameras, and to fuse their informations to obtain 3D coordinates.

2.2.1 Pinhole camera model

Voilà

2.2.2 Calibration

test

2.2.3 Triangulation

suite

2.3 3D joint kinematics

2.3.1 Physically consistent model

autre

2.3.2 Scaling

bref

2.3.3 Inverse kinematics

As opposed to forward kinematics

Compare with 2D angles between 3 points

Different methods (model based vs autres) for angles (cf mail starred)

3

Proposed solution: Pose2Sim Python package

This chapter present our proposed solution, the Pose2Sim python package. This package is meant to constitute a user-friendly bridge between the most common 2D pose detection algorithms, and the OpenSim software so as to provide physically consistent 3D kinematics. Code is available at <https://github.com/perfanalytics/pose2sim>

This chapter is adapted from the article published in the Journal of Open Source Software "Pose2Sim: An Open-source Python Package for multiview markerless kinematics" [Pagnon2022b]

Contents

3.1	Introduction to the workflow	23
3.2	2D pose detection	24
3.3	Pose2Sim core	24
3.3.1	Tracking of the person viewed by the most cameras	24
3.3.2	Triangulating by weighted direct linear transform	24
3.3.3	Filtering	24
3.4	Pose2Sim skeletal model	24
3.5	Limitations and perspectives	24
3.6	Helper functions and vizualisation tools	25

3.1 Introduction to the workflow

Pose2Sim [Pagnon2022b] provides a framework for 3D markerless kinematics, as an alternative to the more usual marker-based motion capture methods. Pose2Sim stands for “OpenPose to OpenSim”, as it uses OpenPose inputs (2D coordinates obtained from multiple videos) [Cao2019] and leads to an OpenSim result (full-body 3D joint angles) [Delp2007, Seth2018]. Pose2Sim is accessible at <https://github.com/perfanalytics/pose2sim>.

The repository presents a framework which consists in (Figures 3.1):

1. Preliminary 2D joint coordinate detections from multiple videos, e.g. with OpenPose.
2. Pose2Sim core, including 4 customizable steps:
 - (a) Camera calibration.
 - (b) 2D tracking of the person of interest.
 - (c) 3D keypoint triangulation, and storage in a .trc file.
 - (d) 3D coordinate filtering.
3. Scaling to each individual subject, and inverse kinematics via OpenSim, and storage of the full-body 3D joint angles.

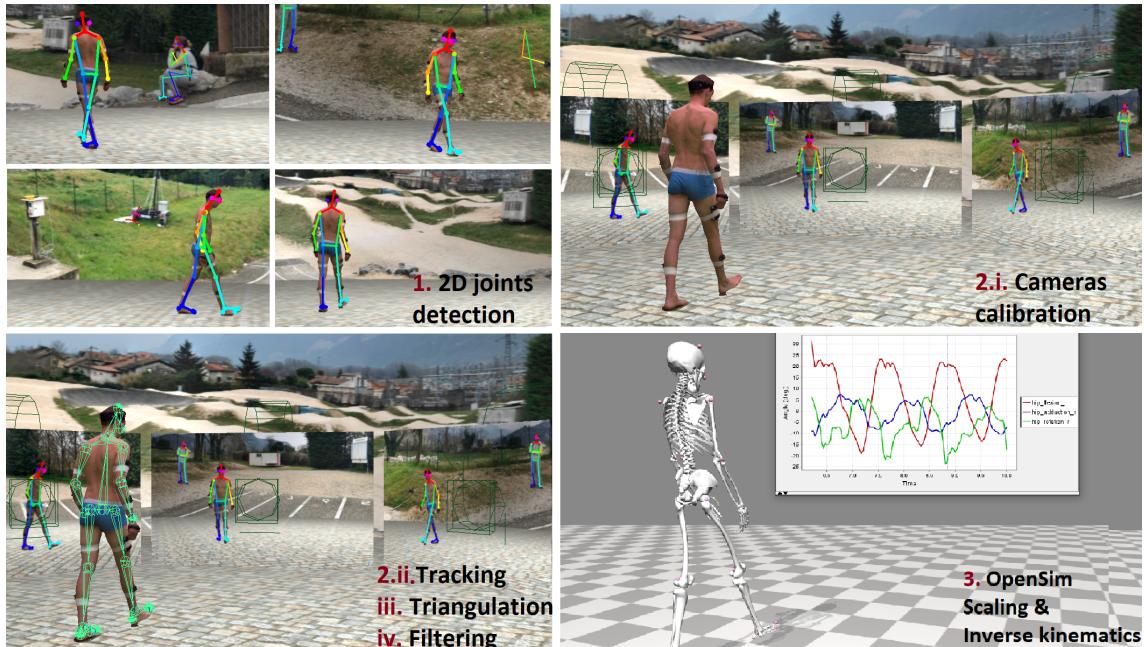


Figure 3.1: Pose2Sim pipeline: (1) 2D joints detection; (2i) camera calibration; (2ii–iv) tracking the person of interest, triangulating their coordinates, and filtering them; (3) scaling the subject, and constraining their 3D coordinates to a physically consistent OpenSim skeletal model

Each task is easily customizable, and requires only moderate Python skills. The whole workflow runs from any video cameras, on any computer, equipped with any operating system (although OpenSim has to be compiled from source on Linux.) Pose2Sim has already been used and tested in a number of situations (walking, running, cycling, dancing, balancing, swimming, boxing), and published in peer-reviewed scientific publications assessing its robustness (see Chapter 4 on [Robustness assessment](#)) [Pagnon2021] and its accuracy (see Chapter 5 on [Accuracy assessment](#)) [Pagnon2022a]. Its results for inverse kinematics were deemed good when compared to marker-based ones, with errors generally below 4.0° across several activities, on both lower and on upper limbs. The combination of its ease of use, customizable parameters, and high robustness and accuracy makes it promising, especially for "in-the-wild" sports movement analysis.

3.2 2D pose detection

3.3 Pose2Sim core

3.3.1 Tracking of the person viewed by the most cameras

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

3.3.2 Triangulating by weighted direct linear transform

3.3.3 Filtering

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

3.4 Pose2Sim skeletal model

A full-body OpenSim [Delp2007, Seth2018] skeletal model with OpenPose keypoints is provided, as well as scaling and inverse kinematics setup files.

OpenSim is another widespread open-source software which helps compute 3D joint angles, usually from marker coordinates. It lets scientists define a detailed musculoskeletal model, scale it to individual subjects, and perform inverse kinematics with customizable biomechanical constraints. It provides other features such as net calculation of joint moments or resolution of individual muscle forces, although this is beyond the scope of our contribution.

3.5 Limitations and perspectives

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

3.6 Helper functions and vizualisation tools

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4

Robustness assessment

Résumé du chapitre possible ici.

Contents

4.1	Introduction	28
4.1.1	Robustness definition	28
4.1.2	Assessing robustness	28
4.2	Methods	28
4.2.1	Experimental setup	28
4.2.2	Participant and protocol	28
4.2.3	Challenging robustness	28
4.2.4	Statistical analysis	29
4.3	Results	29
4.3.1	Data collection and 2D pose estimation	29
4.3.2	Pose2Sim tracking, triangulation, and filtering	29
4.3.3	Relevance, repeatability and robustness of angles Results	29
4.4	Discussion	30
4.4.1	Pose2Sim	30
4.4.2	Relevance, repeatability and robustness	30
4.4.3	Limits and perspectives	30

4.1 Introduction

4.1.1 Robustness definition

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.1.2 Assessing robustness

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.2 Methods

4.2.1 Experimental setup

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.2.2 Participant and protocol

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.2.3 Challenging robustness

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet

and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.2.4 Statistical analysis

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.3 Results

4.3.1 Data collection and 2D pose estimation

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.3.2 Pose2Sim tracking, triangulation, and filtering

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.3.3 Relevance, repeatability and robustness of angles Results

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.4 Discussion

4.4.1 Pose2Sim

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.4.2 Relevance, repeatability and robustness

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

4.4.3 Limits and perspectives

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5

Accuracy assessment

Résumé du chapitre possible ici.

Contents

5.1	Introduction	33
5.1.1	State of the art	33
5.1.2	Assessing accuracy	33
5.2	Methods	33
5.2.1	Data collection	33
5.2.2	Markerless analysis	33
5.2.3	Marker-based analysis	33
5.2.4	Statistical analysis	34
5.3	Results	34
5.3.1	Concurrent validation	34
5.3.2	Comparison with other systems	34
5.4	Discussion	34
5.4.1	Strengths of Pose2Sim and of markerless kinematic	34
5.4.2	Limits and perspectives	35
5.5	Conclusions	35

5.1 Introduction

5.1.1 State of the art

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.1.2 Assessing accuracy

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.2 Methods

5.2.1 Data collection

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.2.2 Markerless analysis

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.2.3 Marker-based analysis

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet

and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.2.4 Statistical analysis

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.3 Results

5.3.1 Concurrent validation

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.3.2 Comparison with other systems

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.4 Discussion

5.4.1 Strengths of Pose2Sim and of markerless kinematic

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.4.2 Limits and perspectives

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

5.5 Conclusions

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6

Application to boxing, using action cameras

Pose2Sim in suboptimal conditions:

Contents

6.1	Objectives	38
6.1.1	Key Performance Indicators in boxing	38
6.1.2	Limits of research-grade systems in competitions	38
6.1.3	Objectives	38
6.2	Methods	38
6.2.1	4 conditions	38
6.2.2	Pose-calibration on ring dimensions	38
6.2.3	Post-synchronization on 2D movement speeds	39
6.2.4	GoPro spatio-temporal base into Qualysis'	39
6.2.5	Statistical analysis	39
6.3	Results	39
6.4	Discussion	39
6.4.1	Equipment and protocol vs. pose estimation model	39
6.4.2	Pros and cons of different systems	40

6.1 Objectives

6.1.1 Key Performance Indicators in boxing

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.1.2 Limits of research-grade systems in competitions

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.1.3 Objectives

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.2 Methods

6.2.1 4 conditions

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.2.2 Pose-calibration on ring dimensions

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet

and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.2.3 Post-synchronization on 2D movement speeds

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.2.4 GoPro spatio-temporal base into Qualysis’

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.2.5 Statistical analysis

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.3 Results

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.4 Discussion

6.4.1 Equipment and protocol vs. pose estimation model

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”?

Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

6.4.2 Pros and cons of different systems

Auto-calibration with person?

Cloud computing?

Temporal consistency?

Shape information for less cameras?

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

7

Application to BMX racing, capturing jointly pilot and bike

Résumé du chapitre possible ici.

Contents

7.1	Introduction	43
7.1.1	The start in BMX racing	43
7.2	Methods	43
7.2.1	Material and protocol	43
7.2.2	Pilot inverse kinematics	43
7.2.3	Bike inverse kinematics	43
7.2.4	Joined pilot and bike inverse kinematics	43
7.3	Results	44
7.4	Discussion	44
7.4.1	On these data	44
7.4.2	Limits and perspectives	44

7.1 Introduction

7.1.1 The start in BMX racing

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

7.2 Methods

7.2.1 Material and protocol

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

7.2.2 Pilot inverse kinematics

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

7.2.3 Bike inverse kinematics

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

7.2.4 Joined pilot and bike inverse kinematics

Marche pas avec nos qualités de vidéo : simulations

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet

and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

7.3 Results

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

7.4 Discussion

7.4.1 On these data

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

7.4.2 Limits and perspectives

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

General conclusion

*C*onclusion here.

Bibliography

- [Ahmad2013] Norhafizan Ahmad, Raja Ariffin Raja Ghazilla, Nazirah M. Khairi et Vijayabaskar Kasi. *Reviews on Various Inertial Measurement Unit (IMU) Sensor Applications*. International Journal of Signal Processing Systems, pages 256–262, 2013.
- [Atha1984] J Atha. *Current techniques for measuring motion*. Applied ergonomics, vol. 15, no. 4, pages 245–257, 1984.
- [Baker2007] Richard Baker. *The history of gait analysis before the advent of modern computers*. Gait and Posture, vol. 26, no. 3, pages 331–342, 9 2007.
- [Bao2022] Yiming Bao, Xu Zhao et Dahong Qian. *FusePose: IMU-Vision Sensor Fusion in Kinematic Space for Parametric Human Pose Estimation*. arXiv preprint arXiv:2208.11960, 2022.
- [Bazarevsky2020] Valentin Bazarevsky, Ivan Grishchenko, Karthik Raveendran, Tyler Zhu, Fan Zhang et Matthias Grundmann. *Blazepose: On-device real-time body pose tracking*. arXiv preprint arXiv:2006.10204, 2020.
- [Benoit2015] D. L. Benoit, M. Damsgaard et M. S. Andersen. *Surface marker cluster translation, rotation, scaling and deformation: Their contribution to soft tissue artefact and impact on knee joint kinematics*. Journal of Biomechanics, vol. 48, no. 10, pages 2124–2129, 7 2015.
- [Bouwmans2019] Thierry Bouwmans, Sajid Javed, Maryam Sultana et Soon Ki Jung. *Deep neural network concepts for background subtraction: A systematic review and comparative evaluation*. Neural Networks, vol. 117, pages 8–66, 2019.
- [Bradski2000] G. Bradski. *The OpenCV Library*. Dr. Dobb’s Journal of Software Tools, 2000.
- [Bridgeman2019] Lewis Bridgeman, Marco Volino, Jean-Yves Guillemaut et Adrian Hilton. *Multi-Person 3D Pose Estimation and Tracking in Sports*. pages 2487–2496, Long Beach, CA, USA, 6 2019. 2019 IEEE/CVF Conference on Computer Vision and Pattern Recognition Workshops (CVPRW), IEEE.
- [Cao2019] Zhe Cao, Gines Hidalgo, Tomas Simon, Shih-En Wei et Yaser Sheikh. *OpenPose: realtime multi-person 2D pose estimation using Part Affinity Fields*. IEEE transactions on pattern analysis and machine intelligence, vol. 43, no. 1, pages 172–186, 2019.
- [Cappozzo1995] A Cappozzo, F Catani, U Della Croce et A Leardini. *Position and orientation in space of bones during movement: anatomical frame*

Bibliography

- definition and determination.* Clinical Biomechanics, vol. 10, no. 4, pages 171–178, 6 1995.
- [Carraro2017] Marco Carraro, Matteo Munaro, Jeff Burke et Emanuele Menegatti. *Real-time marker-less multi-person 3D pose estimation in RGB-Depth camera networks.* arXiv:1710.06235 [cs], 10 2017. arXiv: 1710.06235.
- [Ceseracciu2014] Elena Ceseracciu, Zimi Sawacha et Claudio Cobelli. *Comparison of Markerless and Marker-Based Motion Capture Technologies through Simultaneous Data Collection during Gait: Proof of Concept.* PLoS ONE, vol. 9, no. 3, page e87640, 3 2014.
- [Chambers2015] Ryan Chambers, Tim J Gabbett, Michael H Cole et Adam Beard. *The use of wearable microsensors to quantify sport-specific movements.* Sports medicine, vol. 45, no. 7, pages 1065–1081, 2015.
- [Chen2020] Yucheng Chen, Yingli Tian et Mingyi He. *Monocular human pose estimation: A survey of deep learning-based methods.* Computer Vision and Image Understanding, vol. 192, page 102897, 3 2020.
- [Choppin2013] Simon Choppin et Jonathan Wheat. *The potential of the Microsoft Kinect in sports analysis and biomechanics.* Sports Technology, vol. 6, no. 2, pages 78–85, 5 2013.
- [Chu2021] Hau Chu, Jia-Hong Lee, Yao-Chih Lee, Ching-Hsien Hsu, Jia-Da Li et Chu-Song Chen. *Part-Aware Measurement for Robust Multi-View Multi-Human 3D Pose Estimation and Tracking.* page 10, 2021.
- [Colombel2020] Jessica Colombel, Vincent Bonnet, David Daney, Raphael Dumas, Antoine Seilles et François Charpillet. *Physically Consistent Whole-Body Kinematics Assessment Based on an RGB-D Sensor. Application to Simple Rehabilitation Exercises.* Sensors, vol. 20, no. 10, page 2848, 5 2020.
- [Colyer2018] Steffi L Colyer, Murray Evans, Darren P Cosker et Aki IT Salo. *A review of the evolution of vision-based motion analysis and the integration of advanced computer vision methods towards developing a markerless system.* Sports medicine-open, vol. 4, no. 1, pages 1–15, 2018.
- [Cronin2019] Neil J. Cronin, Timo Rantalainen, Juha P. Ahtiainen, Esa Hynynen et Ben Waller. *Markerless 2D kinematic analysis of underwater running: A deep learning approach.* Journal of Biomechanics, vol. 87, pages 75–82, 4 2019.
- [Cronin2021] Neil J. Cronin. *Using deep neural networks for kinematic analysis: challenges and opportunities.* Journal of Biomechanics, page 110460, 5 2021.
- [D'Antonio2021] Erika D'Antonio, Juri Taborri, Ilaria Miletì, Stefano Rossi et Fabrizio Patane. *Validation of a 3D Markerless System for Gait Analysis based on OpenPose and Two RGB Webcams.* IEEE Sensors Journal, pages 1–1, 2021.

- [della Croce1999] U. della Croce, A. Cappozzo et D. C. Kerrigan. *Pelvis and lower limb anatomical landmark calibration precision and its propagation to bone geometry and joint angles*. Medical and Biological Engineering and Computing, vol. 37, no. 2, pages 155–161, 3 1999.
- [Delp2007] Scott L Delp, Frank C Anderson, Allison S Arnold, Peter Loan, Ayman Habib, Chand T John, Eran Guendelman et Darryl G Thelen. *OpenSim: open-source software to create and analyze dynamic simulations of movement*. IEEE transactions on biomedical engineering, vol. 54, no. 11, pages 1940–1950, 2007.
- [Dong2019] Junting Dong, Wen Jiang, Qixing Huang, Hujun Bao et Xiaowei Zhou. *Fast and Robust Multi-Person 3D Pose Estimation From Multiple Views*. pages 7784–7793, Long Beach, CA, USA, 6 2019. 2019 IEEE/CVF Conference on Computer Vision and Pattern Recognition (CVPR), IEEE.
- [Dong2020] Junting Dong, Qing Shuai, Yuanqing Zhang, Xian Liu, Xiaowei Zhou et Hujun Bao. *Motion Capture from Internet Videos*. In Andrea Vedaldi, Horst Bischof, Thomas Brox et Jan-Michael Frahm, éditeurs, Computer Vision – ECCV 2020, volume 12347, pages 210–227. Springer International Publishing, Cham, 2020.
- [Drazan2021] John F. Drazen, William T. Phillips, Nidhi Seethapathi, Todd J. Hullfish et Josh R. Baxter. *Moving outside the lab: Markerless motion capture accurately quantifies sagittal plane kinematics during the vertical jump*. Journal of Biomechanics, vol. 125, page 110547, 8 2021.
- [Ershadi-Nasab2021] Sara Ershadi-Nasab, Shohreh Kasaei et Esmaeil Sanaei. *Uncalibrated multi-view multiple humans association and 3D pose estimation by adversarial learning*. Multimedia Tools and Applications, vol. 80, no. 2, pages 2461–2488, 1 2021.
- [Fang2017] Hao-Shu Fang, Shuqin Xie, Yu-Wing Tai et Cewu Lu. *RMPE: Regional Multi-person Pose Estimation*. pages 2353–2362, Venice, 10 2017. 2017 IEEE International Conference on Computer Vision (ICCV), IEEE.
- [Fernández-González2020] Pilar Fernández-González, Aikaterini Koutsou, Alicia Cuesta-Gómez, María Carratalá-Tejada, Juan Carlos Miangolarra-Page et Francisco Molina-Rueda. *Reliability of kinovea® software and agreement with a three-dimensional motion system for gait analysis in healthy subjects*. Sensors, vol. 20, no. 11, page 3154, 2020.
- [Fisch2020] Martin Fisch et Ronald Clark. *Orientation Keypoints for 6D Human Pose Estimation*. arXiv:2009.04930 [cs], 9 2020. arXiv: 2009.04930.
- [Geelen2021] Jinne E Geelen, Mariana P Branco, Nick F Ramsey, Frans CT Van Der Helm, Winfred Mugge et Alfred C Schouten. *MarkerLess Motion Capture: ML-MoCap, a low-cost modular multi-camera setup*. In 2021 43rd Annual International Conference of the IEEE Engineering in Medicine & Biology Society (EMBC), pages 4859–4862. IEEE, 2021.

Bibliography

- [Gorton2009] George E. Gorton, David A. Hebert et Mary E. Gannotti. *Assessment of the kinematic variability among 12 motion analysis laboratories.* Gait and Posture, vol. 29, no. 3, pages 398–402, 4 2009.
- [Guo2022] Jiamin Guo, Qin Zhang, Hui Chai et Yibin Li. *Obtaining lower-body Euler angle time series in an accurate way using depth camera relying on Optimized Kinect CNN.* Measurement, vol. 188, page 110461, 2022.
- [Han2013] Jungong Han, Ling Shao, Dong Xu et Jamie Shotton. *Enhanced Computer Vision With Microsoft Kinect Sensor: A Review.* IEEE Transactions on Cybernetics, vol. 43, no. 5, pages 1318–1334, 10 2013. event: IEEE Transactions on Cybernetics.
- [Haralabidis2020] Nicos Haralabidis, David John Saxby, Claudio Pizzolato, Laurie Needham, Dario Cazzola et Clare Minahan. *Fusing Accelerometry with Videography to Monitor the Effect of Fatigue on Punching Performance in Elite Boxers.* Sensors (Basel, Switzerland), vol. 20, no. 20, 10 2020.
- [Hartley1997] Richard I. Hartley et Peter Sturm. *Triangulation.* Computer Vision and Image Understanding, vol. 68, no. 2, pages 146–157, 11 1997.
- [He2020] Yihui He, Rui Yan, Katerina Fragkiadaki et Shoou-I Yu. *Epipolar Transformers.* pages 7776–7785. 2020 IEEE/CVF Conference on Computer Vision and Pattern Recognition (CVPR), 6 2020. ISSN: 2575-7075.
- [Iskakov2019] Karim Iskakov, Egor Burkov, Victor Lempitsky et Yury Malkov. *Learnable Triangulation of Human Pose.* pages 7717–7726, Seoul, Korea (South), 10 2019. 2019 IEEE/CVF International Conference on Computer Vision (ICCV), IEEE.
- [Johnston2019] William Johnston, Martin O'Reilly, Rob Argent et Brian Caulfield. *Reliability, validity and utility of inertial sensor systems for postural control assessment in sport science and medicine applications: a systematic review.* Sports Medicine, vol. 49, no. 5, pages 783–818, 2019.
- [Joo2015] Hanbyul Joo, Hao Liu, Lei Tan, Lin Gui, Bart Nabbe, Iain Matthews, Takeo Kanade, Shohei Nobuhara et Yaser Sheikh. *Panoptic Studio: A Massively Multiview System for Social Motion Capture.* pages 3334–3342. 2015 IEEE International Conference on Computer Vision (ICCV), 12 2015. ISSN: 2380-7504.
- [Kanko2021a] Robert M. Kanko, Elise Laende, W. Scott Selbie et Kevin J. Deluzio. *Inter-session repeatability of markerless motion capture gait kinematics.* Journal of Biomechanics, vol. 121, page 110422, 5 2021.
- [Kanko2021b] Robert M. Kanko, Elise K. Laende, Elysia M. Davis, W. Scott Selbie et Kevin J. Deluzio. *Concurrent assessment of gait kinematics using marker-based and markerless motion capture.* Journal of Biomechanics, page 110665, 8 2021.

- [Karashchuk2021] Pierre Karashchuk, Katie L Rupp, Evyn S Dickinson, Sarah Walling-Bell, Elischa Sanders, Eiman Azim, Bingni W Brunton et John C Tuthill. *Anipose: a toolkit for robust markerless 3D pose estimation.* Cell reports, vol. 36, no. 13, page 109730, 2021.
- [Kidziński2020] Łukasz Kidziński, Bryan Yang, Jennifer L. Hicks, Apoorva Rajagopal, Scott L. Delp et Michael H. Schwartz. *Deep neural networks enable quantitative movement analysis using single-camera videos.* Nature Communications, vol. 11, no. 1, page 4054, 12 2020.
- [Labuguen2020] Rollyn T. Labuguen, Wally Enrico M. Ingco, Salvador Blanco Negrete, Tonan Kogami et Tomohiro Shibata. *Performance Evaluation of Markerless 3D Skeleton Pose Estimates with Pop Dance Motion Sequence.* Rapport technique, 4 2020. DOI: 10.1101/2020.04.15.010702.
- [Leboeuf2019] F. Leboeuf, J. Reay, R. Jones et M. Sangeux. *The effect on conventional gait model kinematics and kinetics of hip joint centre equations in adult healthy gait.* Journal of Biomechanics, vol. 87, pages 167–171, 4 2019.
- [Li2019] Zongmian Li, Jiri Sedlar, Justin Carpentier, Ivan Laptev, Nicolas Mansard et Josef Sivic. *Estimating 3D Motion and Forces of Person-Object Interactions From Monocular Video.* pages 8632–8641, Long Beach, CA, USA, 6 2019. 2019 IEEE/CVF Conference on Computer Vision and Pattern Recognition (CVPR), IEEE.
- [Liao2020] Rijun Liao, Shiqi Yu, Weizhi An et Yongzhen Huang. *A model-based gait recognition method with body pose and human prior knowledge.* Pattern Recognition, vol. 98, page 107069, 2 2020.
- [Liu2022a] Kang Liu, Lingling Chen, Liang Xie, Jian Yin, Shuwei Gan, Ye Yan et Erwei Yin. *Auto calibration of multi-camera system for human pose estimation.* IET Computer Vision, 2022.
- [Liu2022b] Pin-Ling Liu et Chien-Chi Chang. *Simple method integrating Open-Pose and RGB-D camera for identifying 3D body landmark locations in various postures.* International Journal of Industrial Ergonomics, vol. 91, page 103354, 2022.
- [Liu2022c] Wu Liu et Tao Mei. *Recent Advances of Monocular 2D and 3D Human Pose Estimation: A Deep Learning Perspective.* ACM Comput. Surv., mar 2022.
- [Loper2015] Matthew Loper, Naureen Mahmood, Javier Romero, Gerard Pons-Moll et Michael J. Black. *SMPL: a skinned multi-person linear model.* ACM Transactions on Graphics, vol. 34, no. 6, pages 1–16, 11 2015.
- [López-Muñoz2006] Francisco López-Muñoz, Jesús Boya et Cecilio Alamo. *Neuron theory, the cornerstone of neuroscience, on the centenary of the Nobel Prize award to Santiago Ramón y Cajal.* Brain research bulletin, vol. 70, no. 4-6, pages 391–405, 2006.

Bibliography

- [Louis2022] Nathan Louis, Tylan N. Templin, Travis D. Eliason, Daniel P. Nicolella et Jason J. Corso. *Learning to Estimate External Forces of Human Motion in Video*. no. arXiv:2207.05845, Jul 2022.
- [Mathis2018] Alexander Mathis, Pranav Mamidanna, Kevin M. Cury, Taiga Abe, Venkatesh N. Murthy, Mackenzie Weygandt Mathis et Matthias Bethge. *DeepLabCut: markerless pose estimation of user-defined body parts with deep learning*. Nature Neuroscience, vol. 21, no. 9, pages 1281–1289, 9 2018.
- [McCulloch1943] Warren S McCulloch et Walter Pitts. *A logical calculus of the ideas immanent in nervous activity*. The bulletin of mathematical biophysics, vol. 5, no. 4, pages 115–133, 1943.
- [Mehta2020] Dushyant Mehta, Oleksandr Sotnychenko, Franziska Mueller, Weipeng Xu, Mohamed Elgharib, Pascal Fua, Hans-Peter Seidel, Helge Rhodin, Gerard Pons-Moll et Christian Theobalt. *XNect: real-time multi-person 3D motion capture with a single RGB camera*. ACM Transactions on Graphics, vol. 39, no. 4, page 82:82:1–82:82:17, 7 2020.
- [Miller1980] Norman R. Miller, Robert Shapiro et Thomas M. McLaughlin. *A technique for obtaining spatial kinematic parameters of segments of biomechanical systems from cinematographic data*. Journal of Biomechanics, vol. 13, no. 7, pages 535–547, 1 1980.
- [Minaee2021] Shervin Minaee, Yuri Y Boykov, Fatih Porikli, Antonio J Plaza, Nasser Kehtarnavaz et Demetri Terzopoulos. *Image segmentation using deep learning: A survey*. IEEE transactions on pattern analysis and machine intelligence, 2021.
- [Minsky1969] Marvin Minsky et Seymour Papert. *Perceptrons: An introduction to computational geometry*. Cambridge tiass., HIT, vol. 479, page 480, 1969.
- [Mündermann2006] Lars Mündermann, Stefano Corazza et Thomas P. Andriacchi. *The evolution of methods for the capture of human movement leading to markerless motion capture for biomechanical applications*. Journal of NeuroEngineering and Rehabilitation, vol. 3, no. 1, page 6, 3 2006.
- [Nakano2019] Nobuyasu Nakano, Tetsuro Sakura, Kazuhiro Ueda, Leon Omura, Arata Kimura, Yoichi Iino, Senshi Fukashiro et Shinsuke Yoshioka. *Evaluation of 3D markerless motion capture accuracy using Open-Pose with multiple video cameras*. Rapport technique, 11 2019. DOI: 10.1101/842492.
- [Needham2021] Laurie Needham, Murray Evans, Darren P Cosker, Logan Wade, Polly M McGuigan, James L Bilzon et Steffi L Colyer. *The accuracy of several pose estimation methods for 3D joint centre localisation*. Scientific reports, vol. 11, no. 1, pages 1–11, 2021.
- [Novikoff1963] Albert B Novikoff. *On convergence proofs for perceptrons*. Rapport technique, STANFORD RESEARCH INST MENLO PARK CA, 1963.

- [Pagliari2015] Diana Pagliari et Livio Pinto. *Calibration of kinect for xbox one and comparison between the two generations of microsoft sensors.* Sensors, vol. 15, no. 11, pages 27569–27589, 2015.
- [Pagnon2021] David Pagnon, Mathieu Domalain et Lionel Reveret. *Pose2Sim: An End-to-End Workflow for 3D Markerless Sports Kinematics—Part 1: Robustness.* Sensors, vol. 21, no. 19, 2021.
- [Pagnon2022a] David Pagnon, Mathieu Domalain et Lionel Reveret. Sensors, vol. 22, no. 7, 2022.
- [Pagnon2022b] David Pagnon, Mathieu Domalain et Lionel Reveret. *Pose2Sim: An open-source Python package for multiview markerless kinematics.* Journal of Open Source Software, vol. 7, no. 77, page 4362, 2022.
- [Pereira2022] Talmo D Pereira, Nathaniel Tabris, Arie Matsliah, David M Turner, Junyu Li, Shruthi Ravindranath, Eleni S Papadoyannis, Edna Normand, David S Deutsch, Z Yan Wanget al. *SLEAP: A deep learning system for multi-animal pose tracking.* Nature methods, vol. 19, no. 4, pages 486–495, 2022.
- [Rekant2022] Julie Rekant, Scott Rothenberger et April Chambers. *Inertial measurement unit-based motion capture to replace camera-based systems for assessing gait in healthy young adults: Proceed with caution.* Measurement: Sensors, page 100396, 2022.
- [Rempe2020] Davis Rempe, Leonidas J Guibas, Aaron Hertzmann, Bryan Russell, Ruben Villegas et Jimei Yang. *Contact and Human Dynamics from Monocular Video.* page 27, 2020.
- [Rempe2021] Davis Rempe, Tolga Birdal, Aaron Hertzmann, Jimei Yang, Srinath Sridhar et Leonidas J Guibas. *HuMoR: 3D Human Motion Model for Robust Pose Estimation.* page 23, 2021.
- [Reveret2020] Lionel Reveret, Sylvain Chapelle, Franck Quaine et Pierre Legreneur. *3D visualization of body motion in speed climbing.* Frontiers in Psychology, vol. 11, page 2188, 2020.
- [Rosenblatt1958] Frank Rosenblatt. *The perceptron: a probabilistic model for information storage and organization in the brain.* Psychological review, vol. 65, no. 6, page 386, 1958.
- [Seethapathi2019] Nidhi Seethapathi, Shaofei Wang, Rachit Saluja, Gunnar Blohm et Konrad P. Kording. *Movement science needs different pose tracking algorithms.* arXiv:1907.10226 [cs, q-bio], 7 2019. arXiv: 1907.10226.
- [Serrancolí2020] Gil Serrancolí, Peter Bogatikov, Joana Palés Huix, Ainoa Forcada Barberà, Antonio J. Sánchez Egea, Jordi Torner Ribé, Samir Kanaan-Izquierdo et Antoni Susín. *Marker-Less Monitoring Protocol to Analyze Biomechanical Joint Metrics During Pedaling.* IEEE Access, vol. 8, pages 122782–122790, 2020. event: IEEE Access.
- [Seth2018] Ajay Seth, Jennifer L. Hicks, Thomas K. Uchida, Ayman Habib, Christopher L. Dembia, James J. Dunne, Carmichael F.

- Ong, Matthew S. DeMers, Apoorva Rajagopal, Matthew Millard, Samuel R. Hamner, Edith M. Arnold, Jennifer R. Yong, Shrinidhi K. Lakshminikanth, Michael A. Sherman, Joy P. Ku et Scott L. Delp. *OpenSim: Simulating musculoskeletal dynamics and neuromuscular control to study human and animal movement.* PLOS Computational Biology, vol. 14, no. 7, page e1006223, 7 2018.
- [Slembrouck2020] Maarten Slembrouck, Hiep Luong, Joeri Gerlo, Kurt Schütte, Dimitri Van Cauwelaert, Dirk De Clercq, Benedicte Vanwanseele, Peter Veelaert et Wilfried Philips. *Multiview 3D Markerless Human Pose Estimation from OpenPose Skeletons.* In Jacques Blanc-Talon, Patrice Delmas, Wilfried Philips, Dan Popescu et Paul Scheunders, éditeurs, Advanced Concepts for Intelligent Vision Systems, volume 12002, pages 166–178. Springer International Publishing, Cham, 2020.
- [Stenum2021] Jan Stenum, Cristina Rossi et Ryan T. Roemmich. *Two-dimensional video-based analysis of human gait using pose estimation.* PLoS Computational Biology, vol. 17, no. 4, 4 2021.
- [Takahashi2018] Kosuke Takahashi, Dan Mikami, Mariko Isogawa et Hideaki Kimata. *Human Pose as Calibration Pattern: 3D Human Pose Estimation with Multiple Unsyncronized and Uncalibrated Cameras.* pages 1856–18567, Salt Lake City, UT, USA, 6 2018. 2018 IEEE/CVF Conference on Computer Vision and Pattern Recognition Workshops (CVPRW), IEEE.
- [Topley2020] Matt Topley et James G. Richards. *A comparison of currently available optoelectronic motion capture systems.* Journal of Biomechanics, vol. 106, page 109820, 6 2020.
- [Tsushima2003] Hitoshi Tsushima, Meg E Morris et Jennifer McGinley. *Test-Retest Reliability and Inter-Tester Reliability of Kinematic Data from a Three-Dimensional Gait Analysis System.* Journal of the Japanese Physical Therapy Association, vol. 6, no. 1, pages 9–17, 2003.
- [Uhlrich2022] Scott D. Uhlrich, Antoine Falisse, Łukasz Kidziński, Julie Muccini, Michael Ko, Akshay S. Chaudhari, Jennifer L. Hicks et Scott L. Delp. *OpenCap: 3D human movement dynamics from smartphone videos.* page 2022.07.07.499061, Jul 2022.
- [Viswakumar2019] Aditya Viswakumar, Venkateswaran Rajagopalan, Tathagata Ray et Chandu Parimi. *Human Gait Analysis Using OpenPose.* pages 310–314. 2019 Fifth International Conference on Image Information Processing (ICIIP), 11 2019. ISSN: 2640-074X.
- [Wade2021] Logan Wade, Laurie Needham, Murray Evans, Steffi Colyer, Darren Cosker, James Bilzon et Polly McGuigan. *Application of deep learning-based pose estimation methods for clinical gait outcome measures.* In Proceedings of the Congress of the International Society of Biomechanics, Stockholm, Sweden, pages 25–29, 2021.
- [Wang2021] Jinbao Wang, Shujie Tan, Xiantong Zhen, Shuo Xu, Feng Zheng, Zhenyu He et Ling Shao. *Deep 3D human pose estimation: A review.* Computer Vision and Image Understanding, page 103225, 5 2021.

- [Wang2022] Wenming Wang, Kaixiang Zhang, Haopan Ren, Dejian Wei, Yanyan Gao et Juncheng Liu. *UULPN: An ultra-lightweight network for human pose estimation based on unbiased data processing*. Neurocomputing, vol. 480, pages 220–233, 2022.
- [Windt2020] Johann Windt, Kerry MacDonald, David Taylor, Bruno D Zumbo, Ben C Sporer et David T Martin. “*To tech or not to tech?” A critical decision-making framework for implementing technology in sport*. Journal of Athletic Training, vol. 55, no. 9, pages 902–910, 2020.
- [Xu2020] Jingwei Xu, Zhenbo Yu, Bingbing Ni, Jiancheng Yang, Xiaokang Yang et Wenjun Zhang. *Deep kinematics analysis for monocular 3d human pose estimation*. In Proceedings of the IEEE/CVF Conference on computer vision and Pattern recognition, pages 899–908, 2020.
- [Xu2021] Yan Xu, Yu-Jhe Li, Xinshuo Weng et Kris Kitani. *Wide-baseline multi-camera calibration using person re-identification*. In Proceedings of the IEEE/CVF Conference on Computer Vision and Pattern Recognition, pages 13134–13143, 2021.
- [Zago2020] Matteo Zago, Matteo Luzzago, Tommaso Marangoni, Mariolino De Cecco, Marco Tarabini et Manuela Galli. *3D Tracking of Human Motion Using Visual Skeletonization and Stereoscopic Vision*. Frontiers in Bioengineering and Biotechnology, vol. 8, 2020.
- [Zhang2013] Jun-Tian Zhang, Alison C Novak, Brenda Brouwer et Qingguo Li. *Concurrent validation of Xsens MVN measurement of lower limb joint angular kinematics*. Physiological measurement, vol. 34, no. 8, page N63, 2013.
- [Zhang2020] Zhe Zhang, Chunyu Wang, Wenhui Qin et Wenjun Zeng. *Fusing wearable imus with multi-view images for human pose estimation: A geometric approach*. In Proceedings of the IEEE/CVF Conference on Computer Vision and Pattern Recognition, pages 2200–2209, 2020.
- [Zheng2022] Ce Zheng, Wenhan Wu, Taojiannan Yang, Sijie Zhu, Chen Chen, Ruixu Liu, Ju Shen, Nasser Kehtarnavaz et Mubarak Shah. *Deep learning-based human pose estimation: A survey*. arXiv, 2022.

List of Figures

1.1	Principles of marker-based motion capture. (Figure 1.1a) presents the functioning of an opto-electronic camera. (Figure 1.1b) shows how a network of calibrated motion capture cameras helps obtaining joint angles.	4
1.2	IMUs are placed on the subject's limbs. The orientation of the limbs is then used to infer the posture of the subject.	5
1.3	A depth-field camera (RGB-D) projects infrared modulated light onto the subject's body. The time it takes for the light to be reflected to the camera sensor (time of flight) depends on distance, and gives access to the depth of the scene. Older RGB-D cameras use structured light rather than time of flight calculations to infer depth.	6
1.4	The search for “deep learning 3D human pose estimation” (dots) fits an exponential curve (line). The search produced less than 100 results until 2015, and is now well over a 1,000 per year.	7
1.5	2D pose estimation by OpenPose. Image courtesy of [Cao2019].	8
2.1	The artificial neuron has been modeled after the natural neuron. Inputs and weights act as the total nervous influx firing the dendrites. The collected values are summed, and a signal is activated if a threshold is overcome, as the soma does in a natural neuron. The output signal is conveyed through the axon. In the case of a perceptron classifier, the neuron adjusts its weights to minimize the error between the predicted and the expected output.	16
2.2	Classification of athletes as "good" (black dot) or "bad" (circle) according to their Force-Velocity results. Weights are adjusted (grey lines), until the perceptron classifies athletes correctly (black line.)	18
2.3	Single layer artificial neural networks such as the perceptron can only classify linearly separable data. (a) is linearly separable. (b) is not linearly separable. However, data are contained in an ellipse. The equation of an ellipse is of the form $a \times x^2 + b \times y^2 = 1$, so if we transform the feature variables into $X = x^2$ and $Y = y^2$, the data become linearly separable. (c) is equivalent to a fundamental XOR gate, and is not linearly separable, which was part of the reasons for the first AI winter. It can either be solved by combining several layers of artificial neurons, or by complex kernel tricks which map the data from the original space into a higher dimensional space where they become linearly separable. (d) is not linearly separable. AI: Artificial Intelligence. XOR: Exclusive OR.	19
3.1	Pose2Sim pipeline: (1) 2D joints detection; (2i) camera calibration; (2ii–iv) tracking the person of interest, triangulating their coordinates, and filtering them; (3) scaling the subject, and constraining their 3D coordinates to a physically consistent OpenSim skeletal model	23

List of Tables

1.1 Pros and cons in state of the art approaches for human motion analysis. The multi-person prospect is not addressed, as it can be available with all approaches, but it is not always. IMU: Inertial Measurement Unit. N/A: Not Applicable. kin.: kinematic. RGB-D: red-green-blue-depth.	12
--	----

A

Appendix A : Title

Summary here

A.1 Section 1

A.1.1 Sous section 1

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

A.1.2 Sous section 2

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

B

Appendix B : Title

Summary here.

B.1 Section 1

B.1.1 Sous section 1

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

B.1.2 Sous section 2

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

C

Appendix C : Title

Summary here.

C.1 Section 1

C.1.1 Sous section 1

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

C.1.2 Sous section 2

Hello, here is some text without a meaning. This text should show what a printed text will look like at this place. If you read this text, you will get no information. Really? Is there no information? Is there a difference between this text and some nonsense like “Huardest gefburn”? Kjift – not at all! A blind text like this gives you information about the selected font, how the letters are written and an impression of the look. This text should contain all letters of the alphabet and it should be written in of the original language. There is no need for special content, but the length of words should match the language.

"Design, evaluation, and application of a workflow for biomechanically consistent markerless kinematics in sports"

"Conception, évaluation, et application d'une méthode biomécaniquement cohérente de cinématique sans marqueurs en sport"

Résumé

Ici ... résumé en français.

Mots-clés : Mots clés

Abstract

Ici ... résumé en anglais.

Keywords : markerless motion capture; sports performance analysis; kinematics; computer vision; openpose; opensim; python package

