Run TargetDAQ\_UpgradedV16

Setup JR3 adjJR32620xV2

Setup load setup

Initialize DAQ

Zero FM

Enter abduction angle

Enter elbow flexion angle

Enter Arm length

Enter Forearm length

Enter z-offset

Experimental setup:

Abduction 75

Elbow flexion 90

Arm length: acromioclavicular joint to elbow axis of rotation

Forarm length: elbow axis of rotation to middle of bolt along line of fourth finger

z-offset: mark on jr3 to linge between elbow axis of rotation to fourth finger

Target options

Cursor size: 4

pie width: 30% of rotation

dial zero:270

size:4

Hor: 0

Vertical:0

Rotation: how hard to reach target, start at 30

Click on graph, set dial to ef/ee and lock all others

jr3mat=adjJR32620xyV2;

data=totalData';

[m,n] = size(data(:,1:6));

FMhandbase = data(:,1:6) - (diag(FMoffset)\*ones(n,m))';

FMhand = JR3toFMR(FMhandbase(:,1:6),abdAngleR,efAngleR,aLengthR,faLengthR,zOffsetR,jr3mat);

FMhand = [FMhand,data(:,4:8)];

legend('SFE','SAA','SEIR','EFE','WFE')

plot(FMhand)

save(nFileStr,'totalData','FMhand');

jr3mat=adjJR32620xV2;

data=totalData';

[m,n] = size(data(:,1:6));

FMhandbase = data(:,1:6) - (diag(FMoffset)\*ones(n,m))';

FMhand = JR3toFMR(FMhandbase(:,1:6),abdAngleR,efAngleR,aLengthR,faLengthR,zOffsetR,jr3mat);

FMhand = [FMhand,data(:,4:8)];

legend('SFE','SAA','SEIR','EFE','WFE')

plot(FMhand)

save(nFileStr,'totalData','FMhand');

FMhand = JR3toFMR(FMhandbase(:,1:6),abdAngleR,efAngleR,aLengthR,faLengthR,zOffsetR,jr3mat);

save(nFileStr,'totalData')

LivePlotForRamp

close all

clear all

LivePlotForRamp

FMhand = [FMhand,data(:,7)];

legend('SFE','SAA','SEIR','EFE','WFE')

plot(FMhand)

save(nFileStr,'totalData','FMhand');

plot(FMhand(4:8))

legend('SFE','SAA','SEIR','EFE','WFE')

plot(FMhand(:,4:8))

legend('SFE','SAA','SEIR','EFE','WFE')

save(nFileStr,'totalData','FMhand');

First trial started at 39

Last stimulation from first 47

Second 30’’

Started at 47 to 57

Third

Started 57 to 73

Moved distal electrode closer to proximal, repeated 57 to 73

Abd 20 degrees

EF 90 degrees

Arm length 300

Forearm length 157

z-offset 89

right arm