

Towards the Analysis of Movement Variability in Human-Humanoid Imitation Activities



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1. Introduction

Movement variability is an inherent feature within a person and between persons movements [1]. Due to the complexity of the human motion activities and the multi-dimensional variables that are involved in such activities, the use of the non-linear dynamics invariants based on the state space reconstruction have been probed to be reliable techniques for a better insight of movement variability [2]. With this work, we have found that there is little research in the area of human-robot interaction where quantification of movement variability requires to be reliable and create better models of interaction in more realistic scenarios of interaction where the motion capture systems are usually expensive, invasive or take a long-time preparation for calibration.

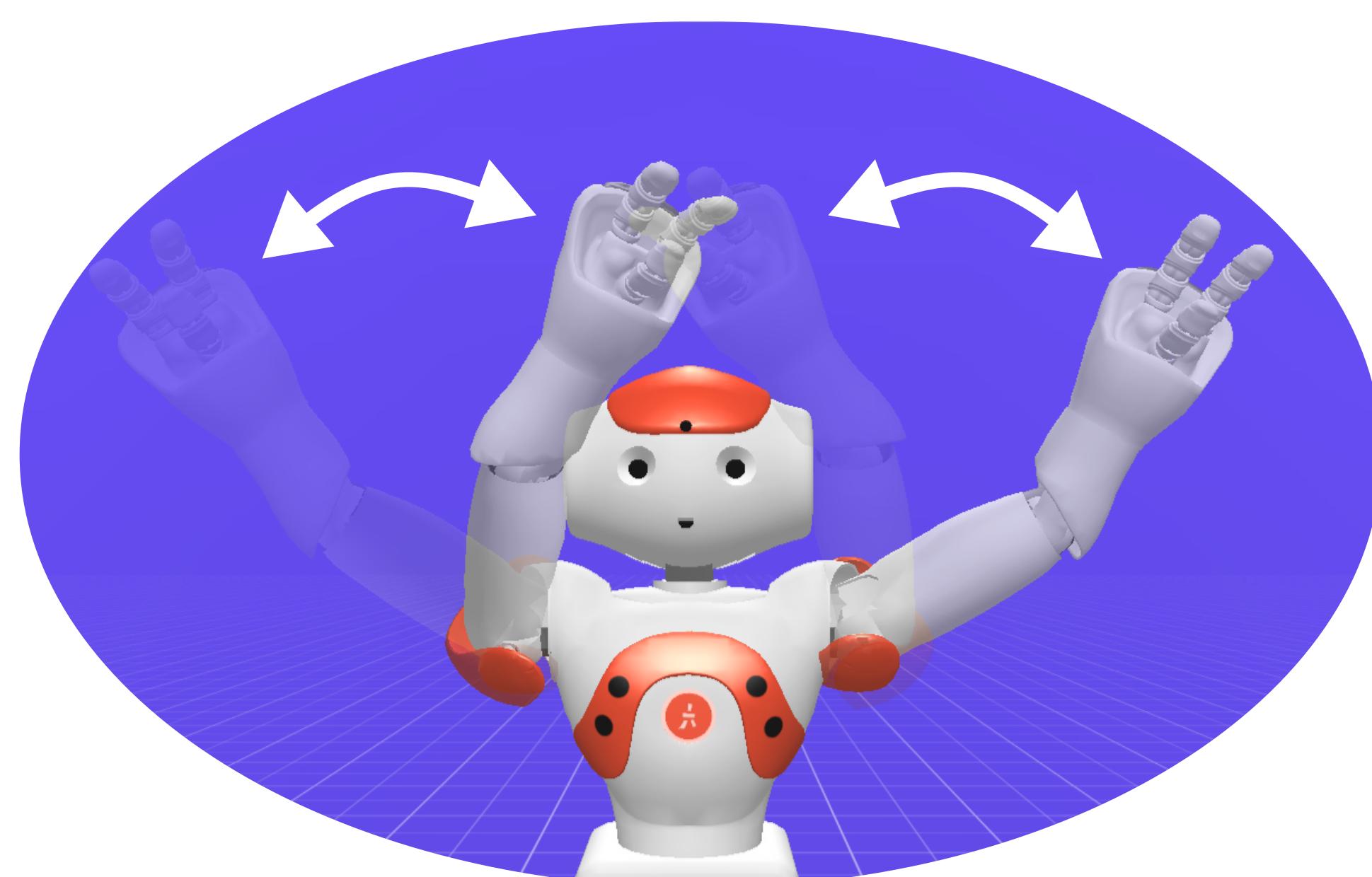


Figure 2. NAO's arm movement

4. Results and Discussion

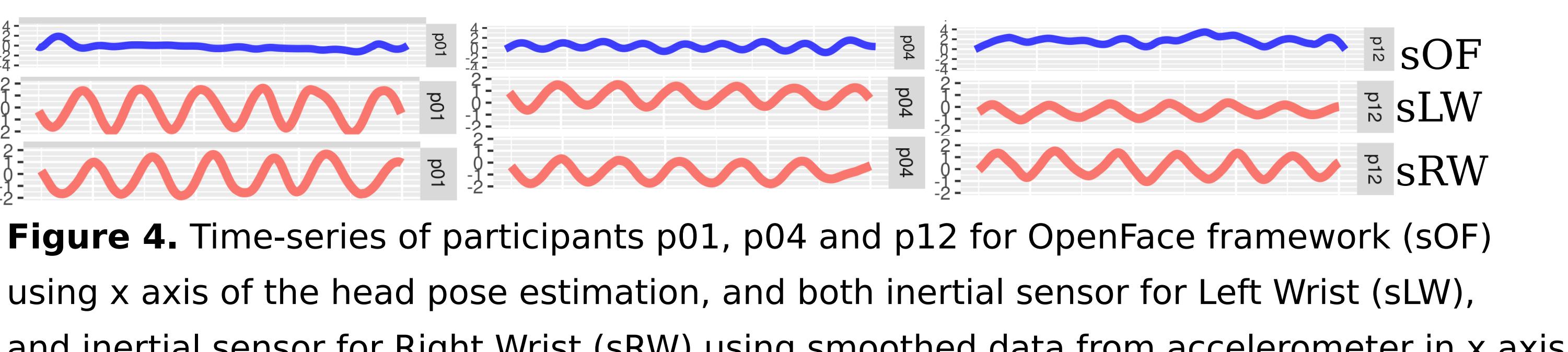


Figure 4. Time-series of participants p01, p04 and p12 for OpenFace framework (sOF) using x axis of the head pose estimation, and both inertial sensor for Left Wrist (sLW), and inertial sensor for Right Wrist (sRW) using smoothed data from accelerometer in x axis.

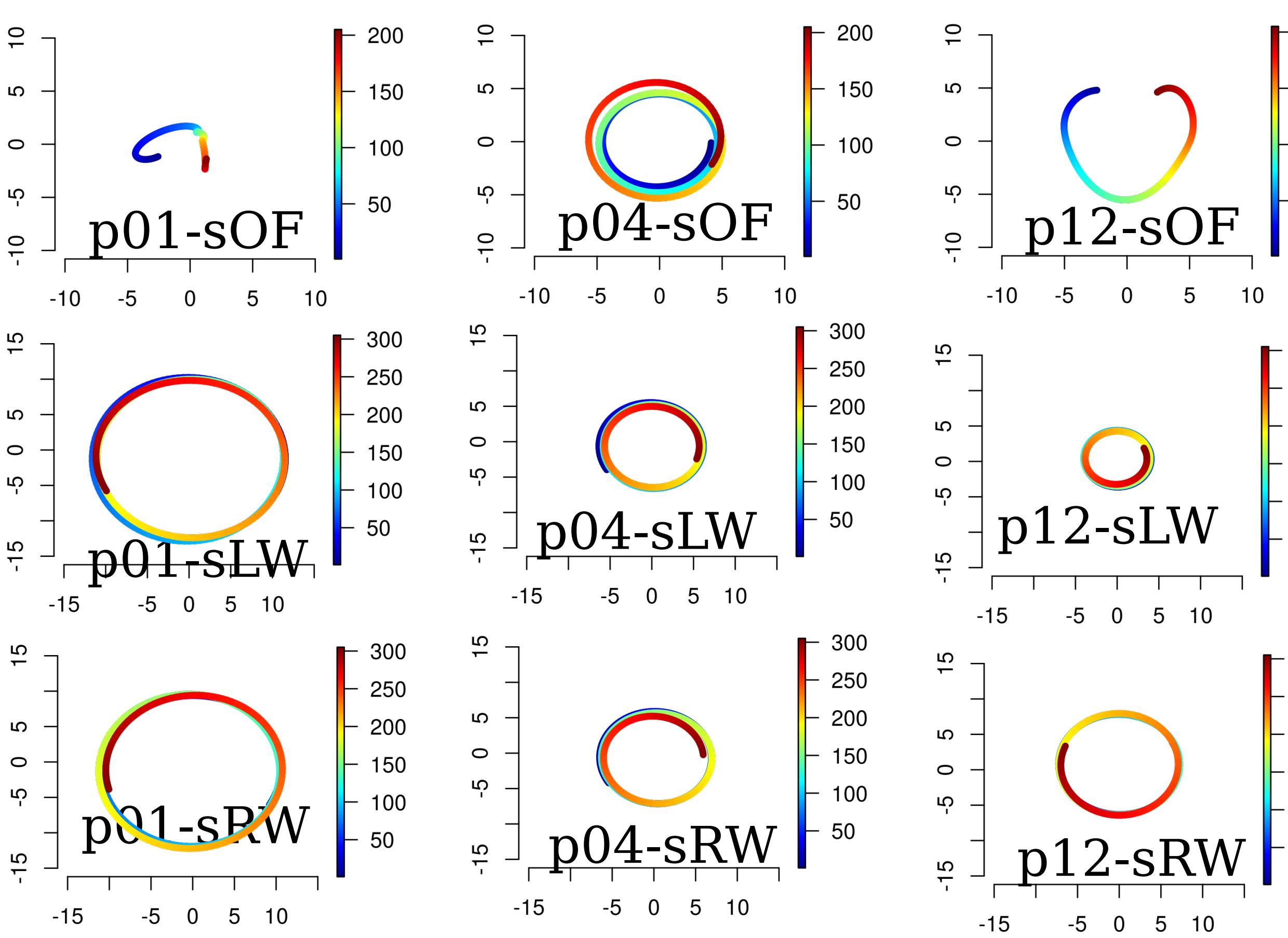


Figure 5. 2-D state space reconstruction with $m = 100$ and $\tau = 4$ for p01, p04 and p12 using the time-series of sOF, sLW and sRW.

6. References

- [1] K. M. Newell and D. M. Corcos. 1993. Variability and Motor Control. Human Kinetics Publishers.
- [2] Juan-Carlos Quintana-Duque. 2012. Non-linear Dynamic Invariants Based on Embedding Reconstruction of Systems for Pedaling Motion. In 9. Symposium der dvs-Sektion Sportinformatik, Univ. Konstanz.
- [3] L. C. Uzal, G. L. Grinblat and P. F. Verdes. 2011. Optimal Reconstruction of dynamical systems: A noise amplification approach. Physical Review E - Statistical Nonlinear and Soft Matter Physics 84, 1 (2011).

2. Methods: State Space Reconstruction's Theorem

The purpose of the State Space Reconstruction's Theorem is to reconstruct an unknown M -dimensional state space from a 1-dimensional measurement function $x(t) = h(s(t))$. The theorem is based on m delayed copies of $x(t)$ uniformly separated by τ . Therefore, the time-delay embedding is defined as a matrix $X(t) = \{x(t), x(t - \tau), x(t - 2\tau), \dots, x(t - (m - 1)\tau)\}$, where (m, τ) are the embedding parameters [3].

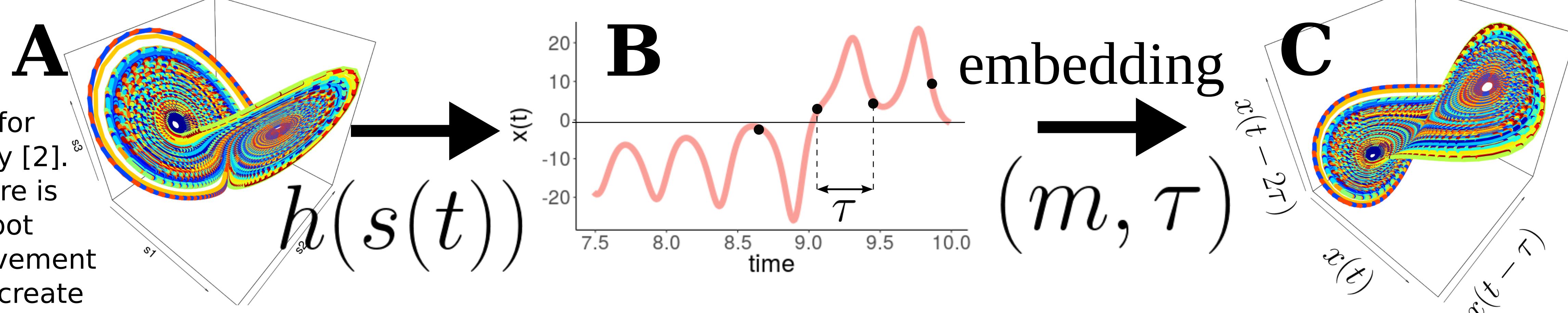


Figure 1. State Space Reconstruction. A. an unknown M -dimensional state space $s(t)$; B. 1-dimensional measured time-series $x(t)$; and C. N -dimensional reconstructed state space $X(t)$ where $M \geq N$.

3. Experiment: Human-Humanoid Imitation Activities



Figure 3. Front to front Human-Humanoid Imitation Activity with upper arm movements of the participant with attached Wearable Inertial sensors. B. OpenFace framework with the landmarks and head pose estimation.

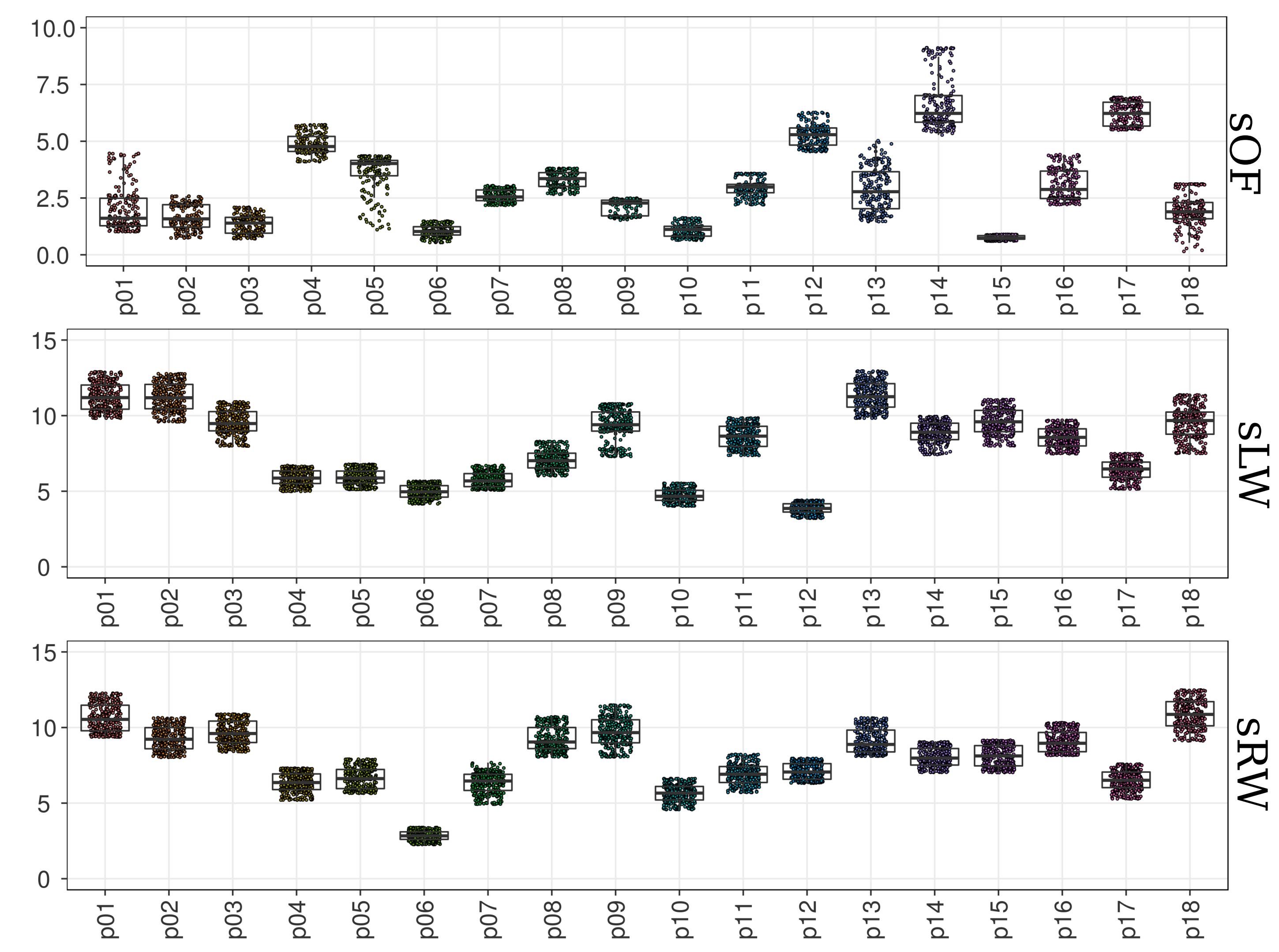


Figure 6. Box and whisker plots for Head Pose estimation, left wrist sensor and right wrist sensor.

5. Conclusion and Future work

We not only presented visual differences of movement variability of arms and head between eighteen participants, but we also quantified such movement

variability using the state space reconstruction's theorem. Considering that the participants were healthy subjects, we quantified that p06 and p12 participants did not imitate NAO well because their arms moved asymmetrically and p04 and p17 moved their head while NAO's head was static. With this in mind, we believe that such results are promising for applications in rehabilitation, sport science, entertainment or education.

In future experiments, we intend to investigate: (i) the variability of emotions and motions in a one-to-one and one-to-many human-humanoid interactions; (ii) exploration of more complex movements; (iii) data collection of wider range of individuals; (iv) application of deep learning techniques for the automatic classification of the movement variability.