

CNeuro 2022
Motor Control and Decision Making Assignment

1. A utility for decisions and movements.

Eq. 1 represents the utility of an action. It is described as a function of α , the reward to be obtained, b , the scaling of effort costs with reward, m , the mass to be moved, d , the distance to be moved, and T , the duration of the movement.

Given the utility, J , use a pencil and paper to obtain an expression for the duration, T^* , that maximizes J . Assume $\alpha, b, m, d > 0$

$$J = \frac{\alpha - bmd/T}{T} \quad [1]$$

2. Investigating the effects of costs and rewards on decisions and movements.

For each of the following exercises, calculate the maximum utility, J^* , the duration, T^* , at which the maximum occurs, and plot utility, J , as a function of movement duration, T , from $T = 0.1$ to 2 s. Start with these parameter values: $\alpha = 100, b = 10, d = 1, m = 1$.

- a) Reward: investigate the effect of doubling reward, α . How do J^* and T^* change with increasing reward?
- b) Effort: investigate the effect of doubling the scaling on effort, b .
- c) Mass: investigate the effect of doubling mass, m .
- d) your turn: try something of your own

3. Utility as a function of reach direction.

This problem has three parts. In part (a) you will calculate the effective mass of the arm as a function of reach direction. In parts (b) and (c), you will use the effective mass to calculate utility, optimal movement duration, and peak velocity as a function of reach direction.

- a) Calculate effective mass of the arm as a function of movement direction.

The effective mass of the arm represents the relationship between a force vector applied to the hand and the resulting acceleration vector measured at the hand at rest. The goal in this module is to calculate and plot the effective mass of the arm in a given static configuration as a function of reach direction. The following explanation will walk you through the process. **The points at which you must explicitly do something are highlighted in bold text.**

The Arm Model

The arm model we use is a two-link planar arm with upper and lower arm segment lengths l_1 and l_2 , and shoulder and elbow joint angles θ_s and θ_e . Model parameters are pulled from standard anthropometric tables:

$$\begin{aligned}
l_1 &= 0.33, \text{ length of upper arm, meters} \\
l_2 &= 1.3l_1, \text{ length of forearm} \\
lc_1 &= l_1/2, \text{ center of mass for upper arm} \\
lc_2 &= 2l_2/3, \text{ center of mass for forearm} \\
m_1 &= 1.93, \text{ mass of upper arm, kg} \\
m_2 &= 1.52, \text{ mass of forearm} \\
i_1 &= 0.0141, \text{ inertia of upper arm, kg.m}^2 \\
i_2 &= 0.01882, \text{ inertia of forearm}
\end{aligned}$$

The initial arm configuration is set to match the experimental conditions in Gordon et al. 1982:

$$\theta_s = 0.994 \quad \theta_e = 1.5724$$

Using trigonometry, we define $x = [h_x, h_y]^T$, a vector of hand position as a function of joint angles θ_s and θ_e :

$$x = \begin{bmatrix} h_x \\ h_y \end{bmatrix} = \begin{bmatrix} l_1 \cos \theta_s + l_2 \cos(\theta_s + \theta_e) \\ l_1 \sin \theta_s + l_2 \sin(\theta_s + \theta_e) \end{bmatrix} \quad [2]$$

Effective Mass

To start, we determine the inertia of the arm. The inertia in this case is a 2x2 position dependent matrix:

$$I(\theta) = \begin{bmatrix} I_{11} & I_{12} \\ I_{21} & I_{22} \end{bmatrix},$$

where θ is a vector that includes the instantaneous shoulder and elbow angles, $\theta = [\theta_s, \theta_e]^T$.

We have

$$\begin{aligned}
I_{11} &= a_3 + a_1 l_1^2 + a_4 + 2a_2 l_1 \cos \theta_e \\
I_{12} &= I_{21} = a_2 + l_1 \cos \theta_e + a_4 \\
I_{22} &= a_4 \\
a_1 &= m_2 \\
a_2 &= m_2 lc_2 \\
a_3 &= m_1 lc_1^2 + i_1 \\
a_4 &= m_2 lc_2^2 + i_2
\end{aligned}$$

When the arm is at rest, the inertial matrix describes the relationship between joint torques at the shoulder and elbow, and the resulting joint accelerations:

$$\tau = I(\theta)\ddot{\theta} \quad [3]$$

Our goal is to identify the relationship, $M(\theta)$, between forces at the hand as measured at rest and the resulting accelerations:

$$f = M(\theta)\ddot{x} \quad [4]$$

To calculate $M(\theta)$ we use the Jacobian matrix, $\Lambda = dx/d\theta$. To calculate the Jacobian, we return to the relationship between hand and joint coordinates (Eq. 2) and take the derivative with respect to the joint angle vector, θ :

$$\Lambda = \frac{dx}{d\theta} = \begin{bmatrix} \frac{\partial h_x}{\partial \theta_s} & \frac{\partial h_x}{\partial \theta_e} \\ \frac{\partial h_y}{\partial \theta_s} & \frac{\partial h_y}{\partial \theta_e} \end{bmatrix} \quad [5]$$

a.1) Obtain an expression for the Jacobian, Λ .

We then use the principle of virtual work and relate joint torques to forces at the hand:

$$\tau^T \Delta\theta = f^T \Delta x \quad [6]$$

Rearranging terms leads to an expression that allows us to compute the joint torques resulting from a force at the hand:

$$\begin{aligned} \tau^T &= f^T \frac{\Delta x}{\Delta\theta} = f^T \Lambda \\ \tau &= \Lambda^T f \end{aligned} \quad [7]$$

Combining Eq. 3 and Eq. 7, and using the following relationships:

$$\begin{aligned} \dot{x} &= \Lambda \dot{\theta} \quad \Rightarrow \quad \dot{\theta} = \Lambda^{-1} \dot{x} \\ \ddot{x} &= \Lambda \ddot{\theta} + \dot{\Lambda} \dot{\theta} \quad \Rightarrow \quad \ddot{\theta} = \Lambda^{-1} (\ddot{x} - \dot{\Lambda} \dot{\theta}) \end{aligned} \quad [8]$$

we obtain:

$$f = \Lambda^{-1T} I(\theta) \Lambda^{-1} (\ddot{x} - \dot{\Lambda} \dot{\theta}) \quad [9]$$

The hand is at rest so the velocity term is zero, leaving us with:

$$f = \Lambda^{-1T} I(\theta) \Lambda^{-1} \ddot{x} \quad [10]$$

From Eq. 4, we see that this provides us with an expression for the mass matrix, $M(\theta)$, relating acceleration and forces measured at the hand at rest:

$$M(\theta) = \Lambda^{-1T} I(\theta) \Lambda^{-1}$$

a.2) Calculate $M(\theta)$ for the given arm configuration.

We obtain the effective mass, m , in a given reach direction by applying a unit vector acceleration in the given reach direction and calculating the length of the resultant force vector.

a.3) Calculate effective mass of the arm for reach directions $\theta_r = 0$ to 2π rad, where θ_r is measured with respect to the positive x-axis. On a polar plot, plot effective mass as a function of reach direction.

b) Using the effective mass calculated in module 3.a and the equations for utility (Eq. 1) and optimal duration in Question 1, plot optimal duration as a function of movement direction. Use these parameters in the utility equation: $\alpha = 50$, $b = 100$, and $d = 0.1$.

c) Plot peak movement velocity as a function of movement direction. Peak velocity can be estimated for a movement of a given duration and distance using the kinematics predicted by a minimum jerk trajectory (Flash and Hogan 1985). Use the m-file provided (minjerk.m) to calculate peak velocity for a movement of given direction and duration. You can also write your own program in the language of your choice based on the template below. Compare with results in Gordon et al. 1994. (Fig. 1A below)

[time,r,v,a,]=minjerk(r_i,r_f,dur,ts)

r_i : 2x1 x,y coordinates of start position [x_i , y_i]; e.g. $r_i = [0; 0]$ for a movement start at the origin

r_f: 2x1 x,y coordinates of end position [x_f , y_f]; e.g. $r_f = [0; 0.1]$ for a 10 cm movement

dur: duration of movement; e.g. $dur = 0.5s$

ts: sample time; e.g. $ts = 0.01$

r, v, a: $n \times 2$ position, velocity and acceleration vectors, where $n=dur/ts$

time: $n \times 1$ time vector, where $n=dur/ts$

% calculate normalized time vector

$\tau = time/dur$

% calculate x and y position trajectories

$\mathbf{x(t)} = x_i + (x_i - x_f)(15\tau^4 - 6\tau^5 - 10\tau^3)$

$\mathbf{y(t)} = y_i + (y_i - y_f)(15\tau^4 - 6\tau^5 - 10\tau^3)$

% calculate x and y velocity trajectories

$\mathbf{x\dot{d}ot(t)} = (x_i - x_f)(60\tau^3 - 30\tau^4 - 30\tau^2)/dur$

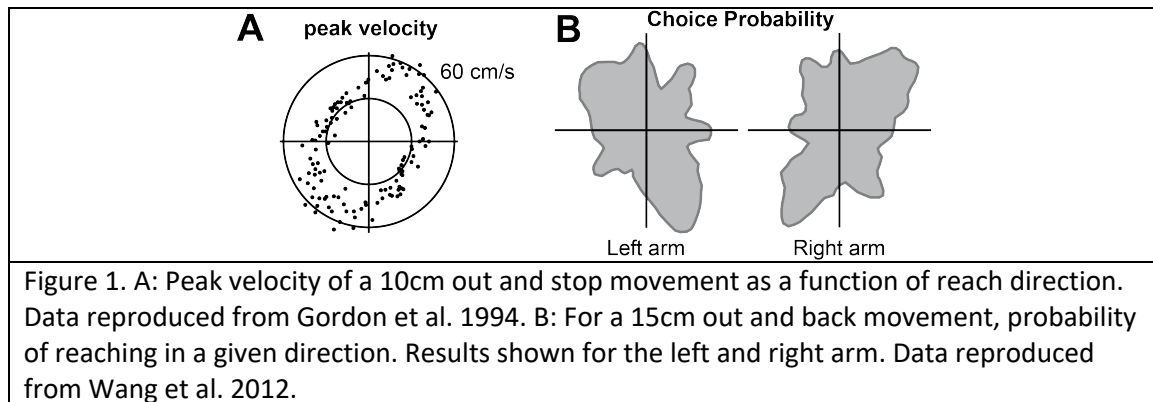
$\mathbf{y\dot{d}ot(t)} = (y_i - y_f)(60\tau^3 - 30\tau^4 - 30\tau^2)/dur$

% calculate x and y acceleration trajectories (optional)

$\mathbf{x\ddot{d}ot(t)} = (x_i - x_f)(180\tau^2 - 120\tau^3 - 60\tau)/(dur^2)$

$\mathbf{y\ddot{d}ot(t)} = (y_i - y_f)(180\tau^2 - 120\tau^3 - 60\tau)/(dur^2)$

d) Natalia Dounskaia and colleagues asked subjects to make 15cm out-and-back reaching movements in any direction they preferred and measured the probability with which they chose to reach in a given direction for both arms (Wang et al. 2012). We have provided a .mat file (effMassDounskaia.mat) and .csv file (effMassDounskaia.csv) with the effective mass for the left and right arm for an out-and-back movement for reaching directions $\theta_{reach} = 0:\pi/32:2\pi$. Calculate the probability as a function of reach direction using Eq. 1. Use the following parameters: $\alpha = 50$, $b = 100$, and $d = 0.15$. Compare to Wang et al. 2012 (Fig. 1B below).



References

Flash, T. and Hogan, N. (1985). The coordination of arm movements: an experimentally confirmed model. *J Neurosci* 5, 1688-1703.

Gordon, J., Ghilardi, M. F., Cooper, S. E., and Ghez, C. (1994). Accuracy of Planar Reaching Movements. II. Systematic Extent Errors Resulting From Inertial Anisotropy. *Exp Brain Res* 99, 112–130.

Wang, W. and Dounskaia, N. (2012). Load emphasizes muscle effort minimization during selection of arm movement direction. *J Neuroeng Rehabil* 9, 1–1.