

# Responses to locomotion commotion caused by translation perturbations



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## Motivation

### How do humans navigate non-steady-state environments?

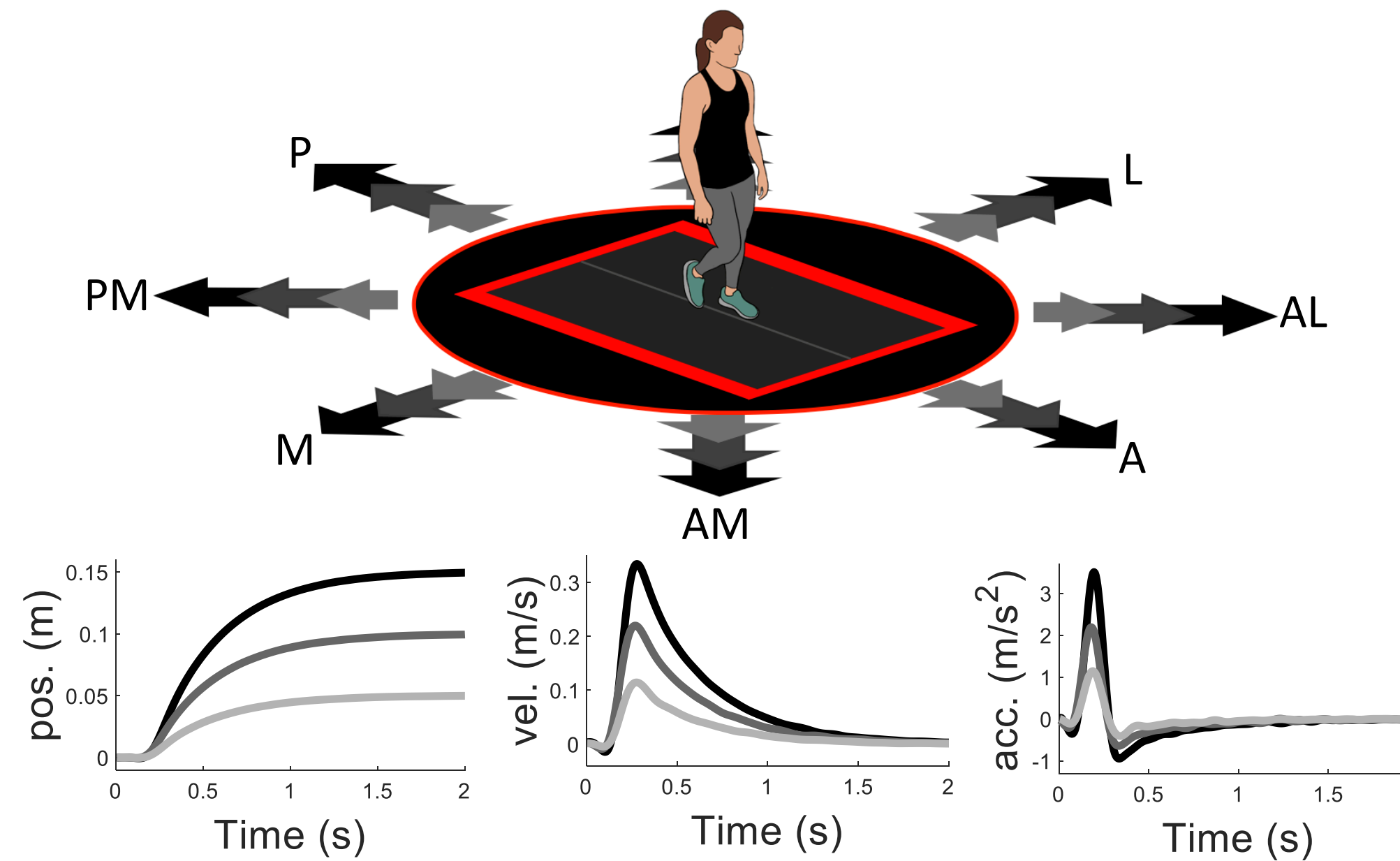
An understanding of stability could aid in

- Assessing and assisting impaired populations [1]
- Creating assistive and augmentative devices [2]
- Controlling legged robots in diverse environments

Perturbation recovery strategy is indicated by:

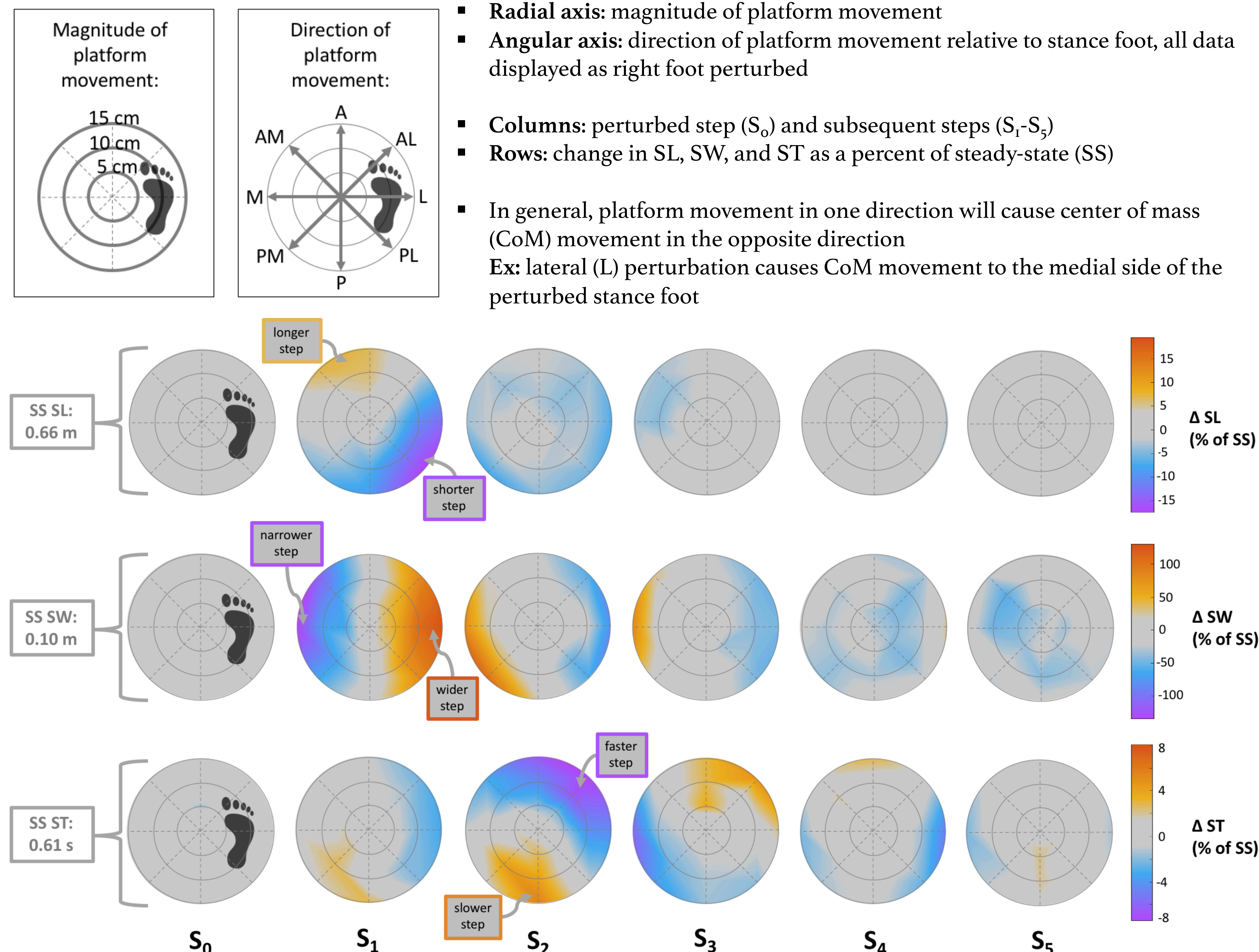
- Step length (SL)
- Step width (SW)
- Step time (ST)

## Methods



- N = 1
- Walking speed: 1.25 m/s
- Perturb subject by translating walking platform (24 conditions)
  - Magnitudes: 5, 10, 15 cm
  - Directions: 45° increments
  - (24 conditions) x (12 repetitions) = 288 perturbations
- Collected kinematics
- Identified gait events using kinematic coordinate method [3]
- Calculated step length (SL), step width (SW), and step time (ST) for the perturbed step ( $S_0$ ) and subsequent steps ( $S_1$ - $S_5$ )

## Results



## Discussion

### Step length:

- Most affected on the  $S_1$  step, trends last 1-2 steps
- Shorter steps with PL perturbations (up to -18%), longer steps with AM perturbations (up to +7%)

### Step width:

- Most affected on the  $S_1$  step, trends last 2-3 steps
- Narrower steps with M perturbations (up to -135%), wider steps with L perturbations (up to +129%)

### Step time:

- Most affected on the  $S_2$  step, trends last 3-4 steps
- Faster steps with AL perturbations (up to -7%), slower steps with P perturbations (up to 6%)

**Humans modulate SL, SW, and ST in response to perturbations**

**Largest changes to SL, SW, and ST are not elicited by the same perturbation conditions**

## References

- [1] S. M. Bruijn, et al., *J. R. Soc. Interface* 10, (2013)
- [2] D. Tokur, et al., *Hum. Movement Sci.* 69, (2020)
- [3] J. A. Zeni, et al., *Gait Posture* 27, (2008)

## Acknowledgements

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