

Background

- Loss of stability and falls are a major public health concern
- US workplace falls cost \$8.6 billion in 2010 [1]
- 25% of adults > 65 years old fall each year [2]
- Wearable robots can help address balance problems:
 - Point in gait cycle when people are least stable is unknown
- Compromised balance is indicated and measured by:
 - Increased dynamic stability margin [3]
 - Increased step width [4]
 - Decreased step length [4]

Hypothesis

People are least stable to forward slips between 15 and 20% of the gait cycle

Methods

- 10 subjects walked on a split-belt treadmill (Fig 1A)
- Belt slips were applied 10x to each leg at 6 times
 - 10, 15, 20, 30, 40, and 50% gait cycle (Fig 1B)
- Balance metrics were calculated from motion capture (Fig 1C)

Slip Examples

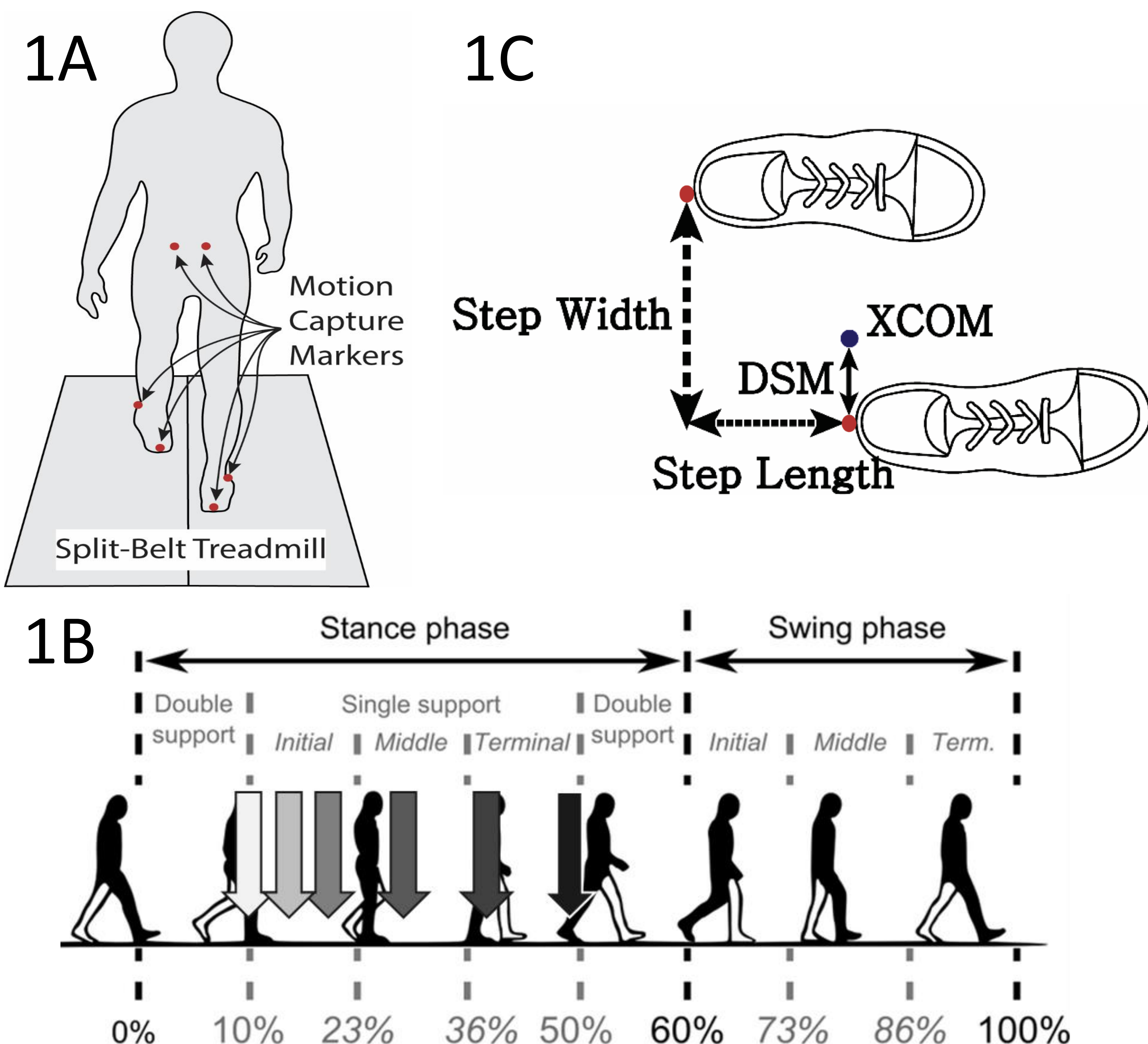


Figure 1A – Experimental setup, Figure 1B – Slip timings during the gait cycle, Figure 1C – Stability metrics

Results

- “*” in Fig 2 represents that slip timing had a significant effect on that step
- Bars in Fig 2 represent two timings were significantly different
- “L” represents value is normalized to leg length

Dynamic Stability Margin (Fig 2A)

- Larger during first step after 20 and 30% slips

Step Width (Fig 2B)

- Larger during second and third steps after 20% slips

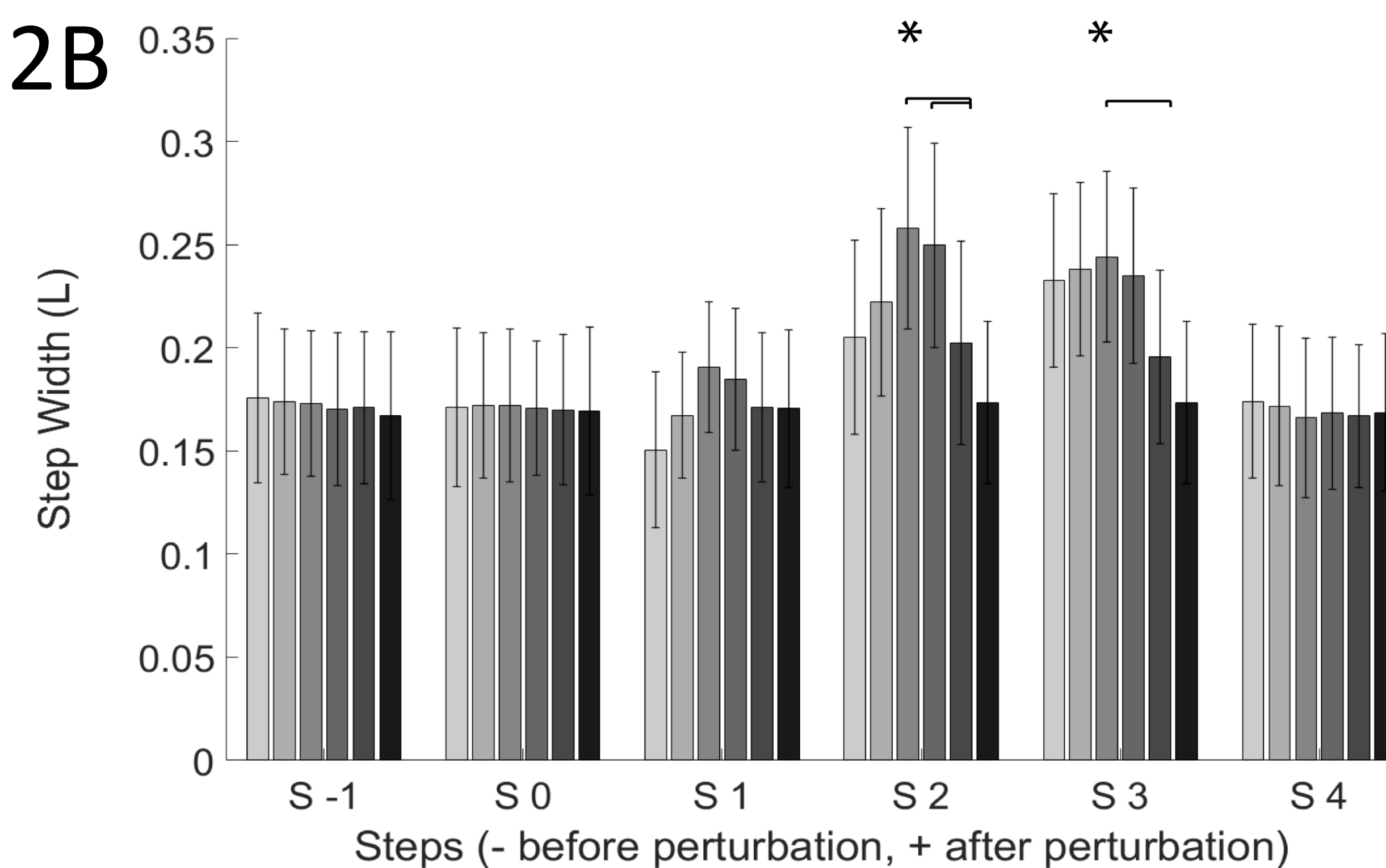
Step Length (Fig 2C)

- Lower during second step after 20 and 30% slips

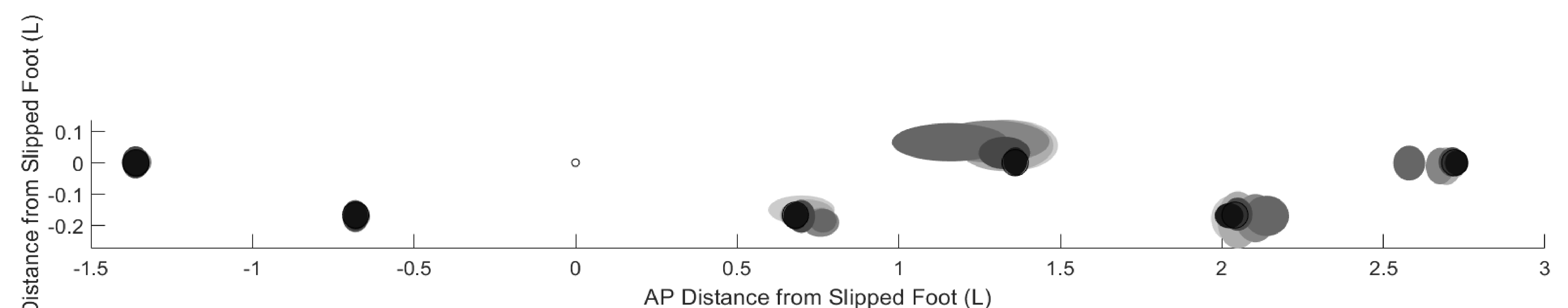
Foot Placement (Fig 2D)

- Most different for second step after 30% slips

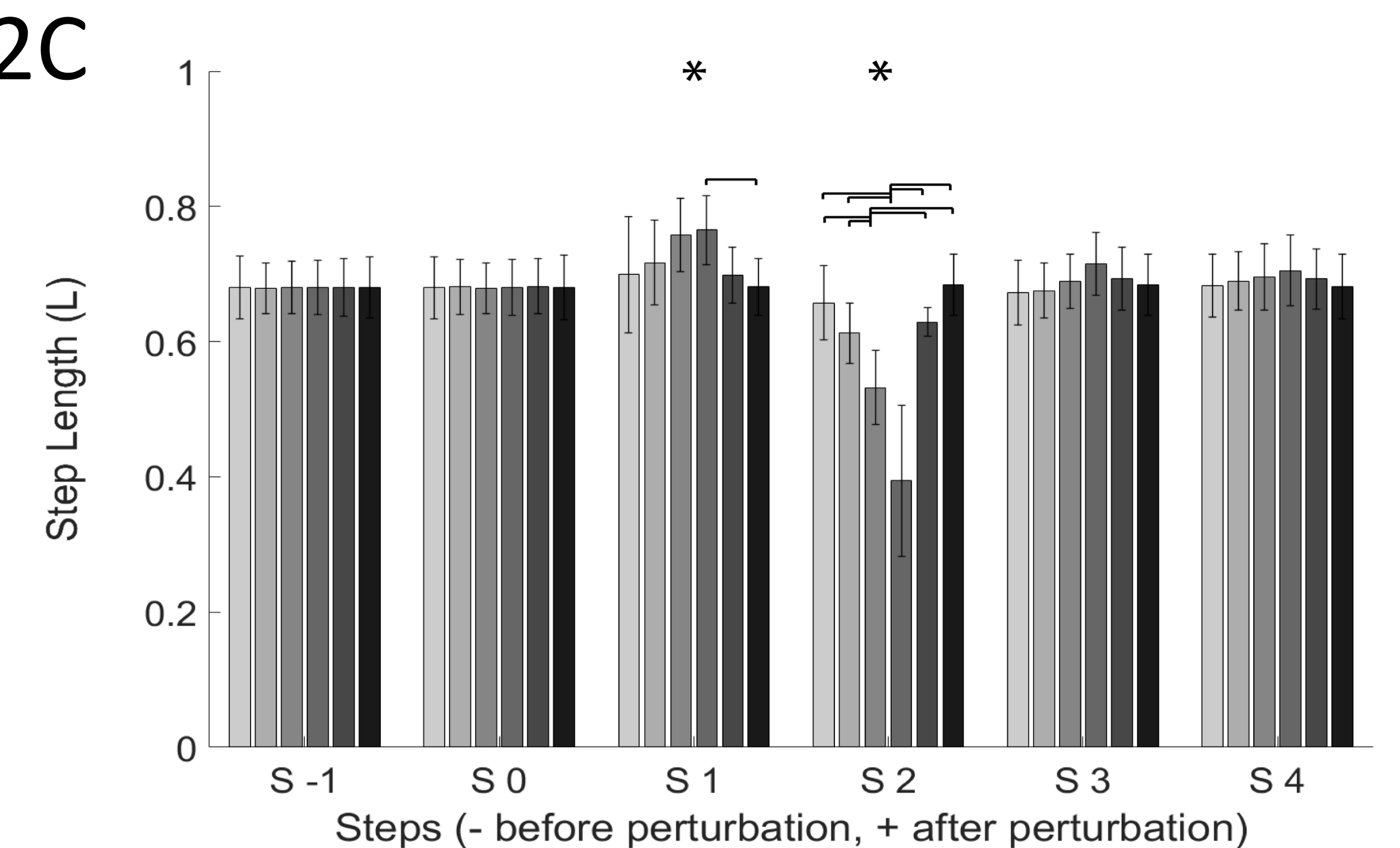
2B



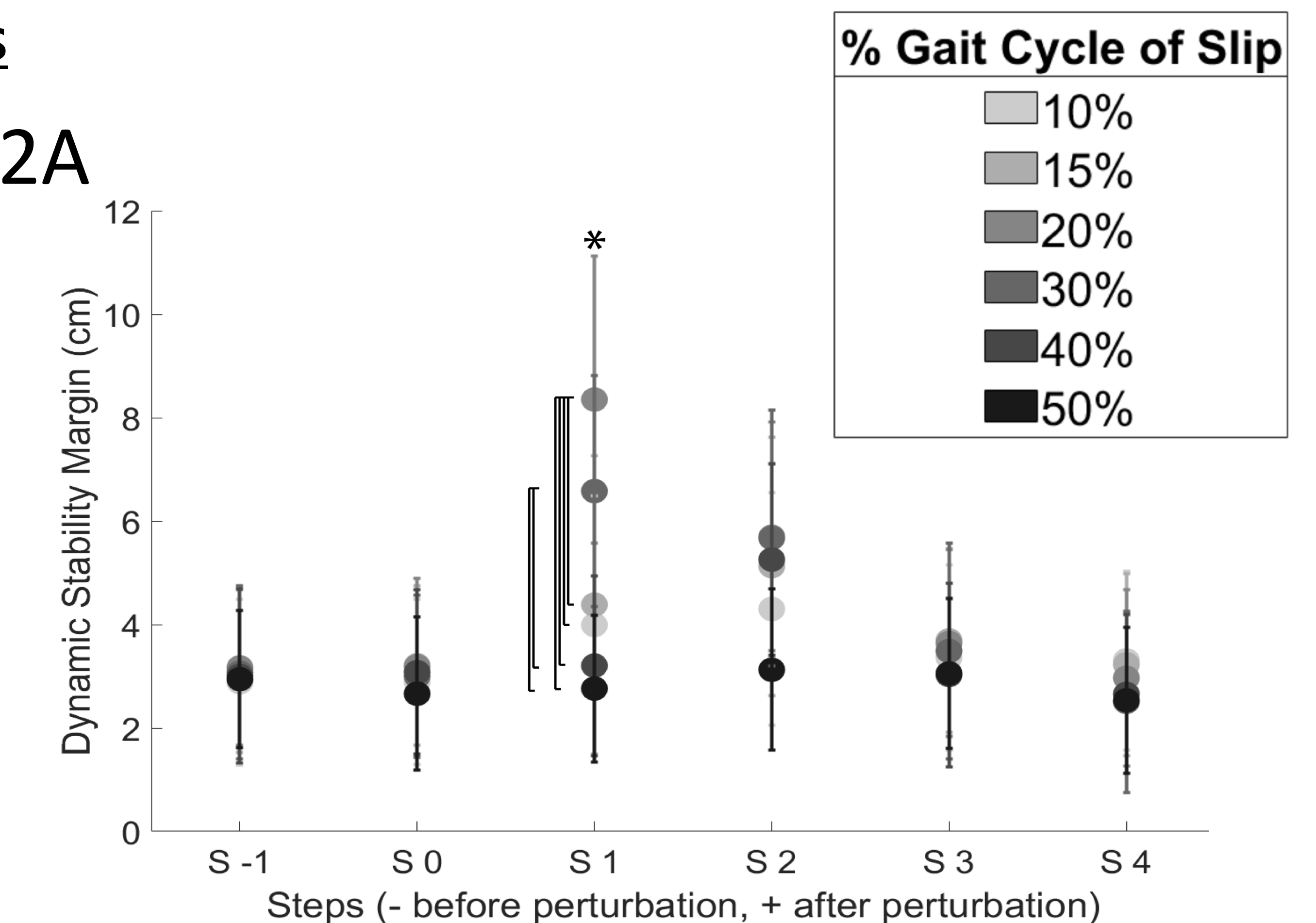
2D



2C



2A



Key Take-Away Points

- People are least stable to forward slips between 20-30% of the gait cycle
- Slips at 20% influence width more than length of foot placement
- Slips at 30% influence length more than width of foot placement

References