Human Motor Systems
(Part 2)

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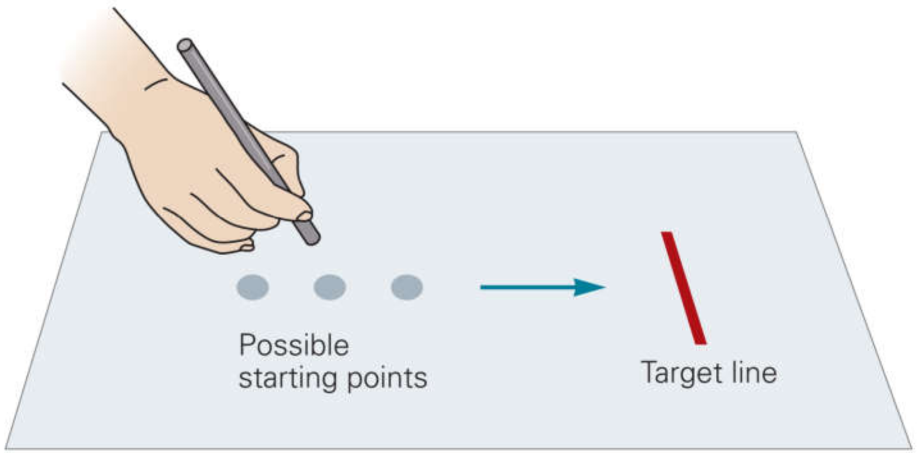
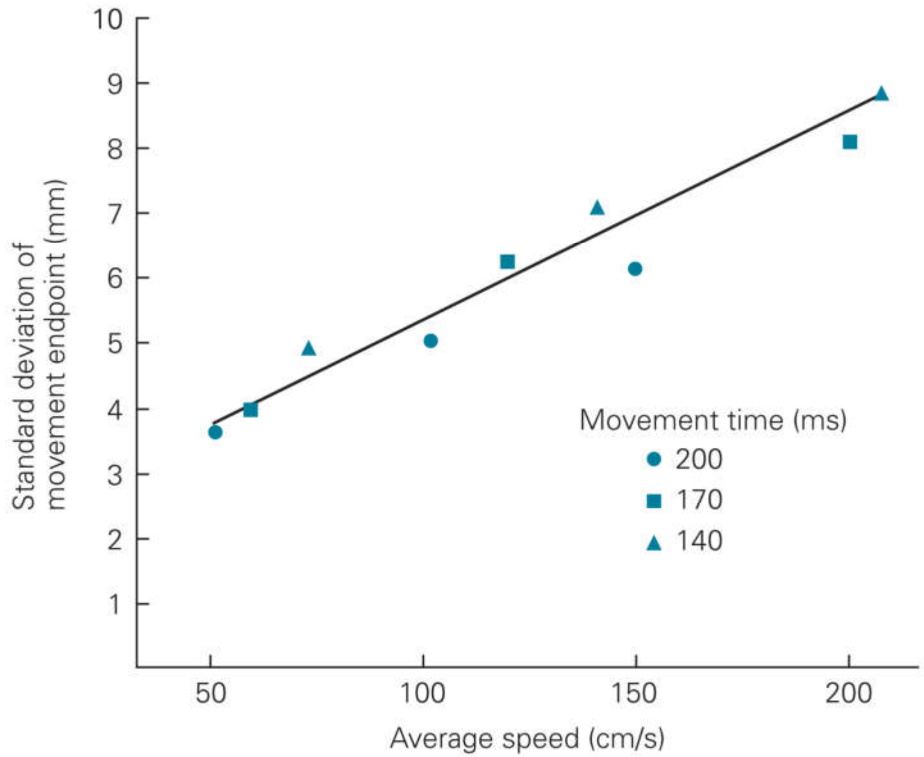
Kinematic regularity

- The speed-accuracy trade-off



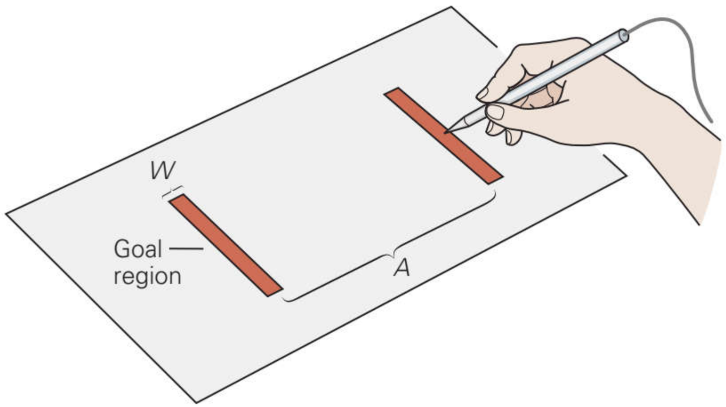


- Three initial positons
- Different movement times (140, 170, or 200ms)
- Variability in proportion to speed (force)

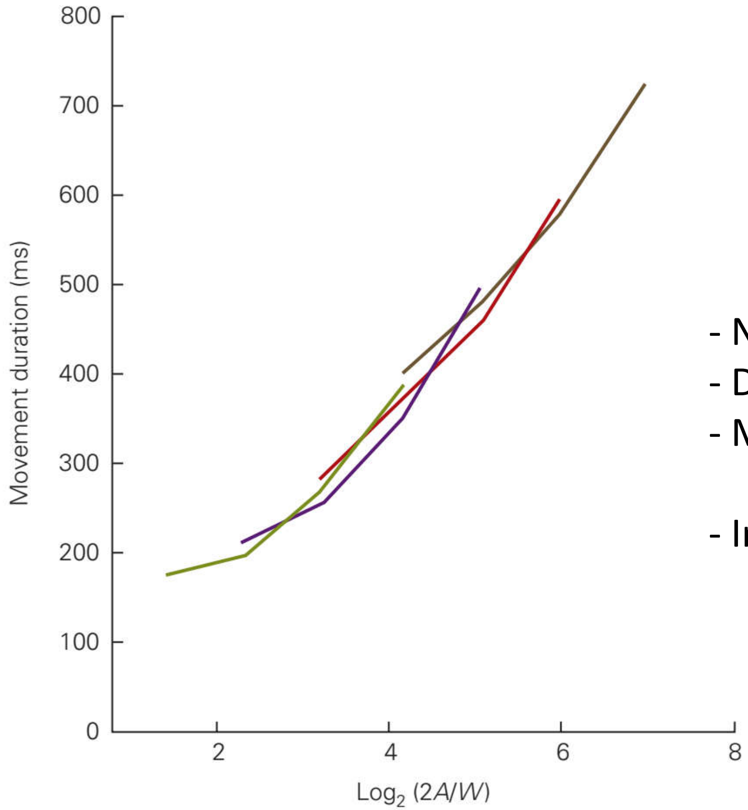
Kandel et al. Figure 33-4

Kinematic regularity

- Fitt's law describes the speed-accuracy trade-off



$$Movement\ duration = a + b * log_2(\frac{2A}{W})$$



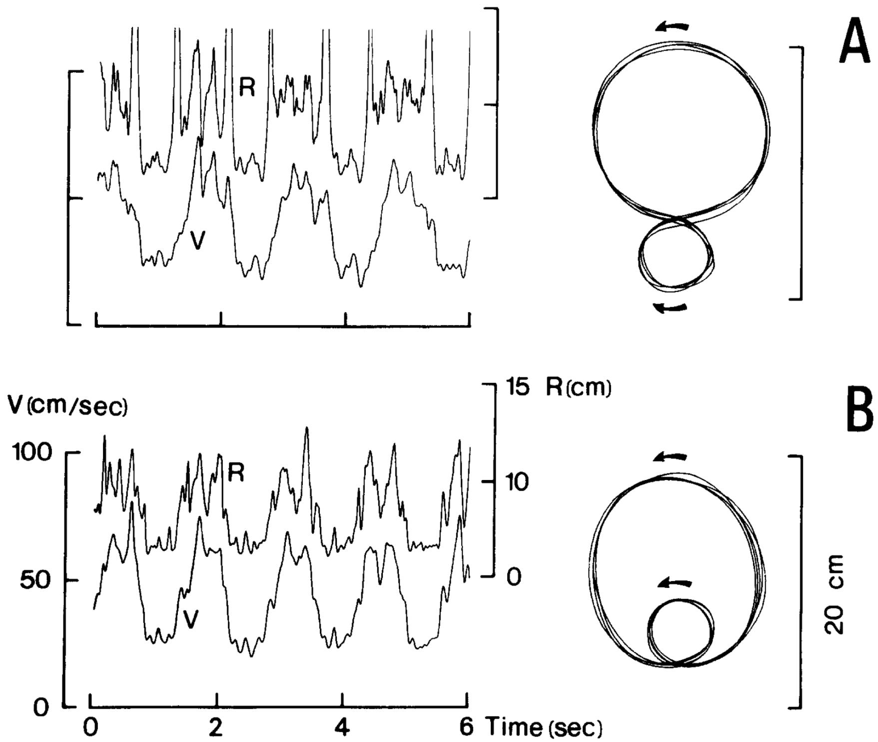
- Narrow and wide targets (W)
- Different distances (A)
- Move as fast as possible

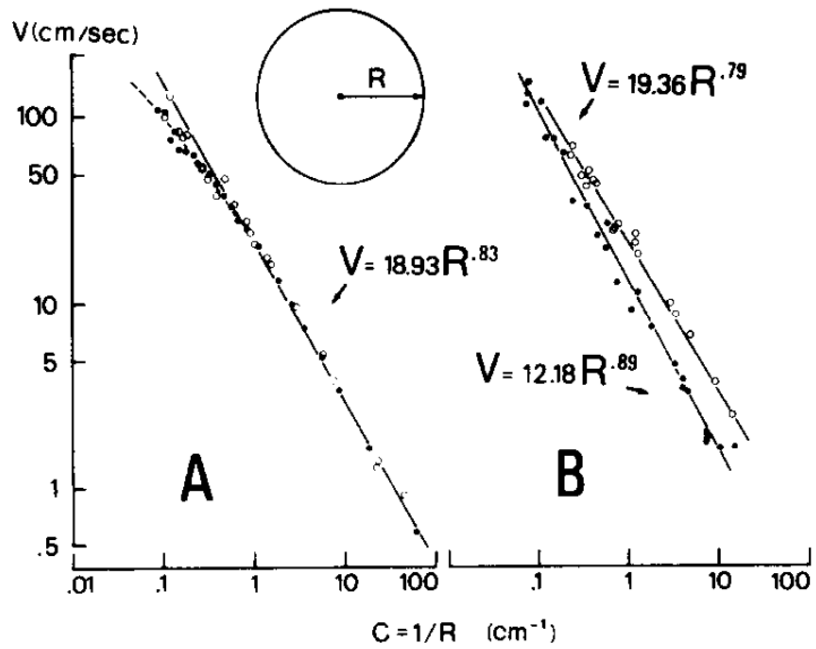
- Index of difficulty: $log_2(\frac{2A}{W})$

Kandel et al. Figure 33-8

Kinematic regularity

- Velocity* (V) vs. curvature (C) obeys “power-law”



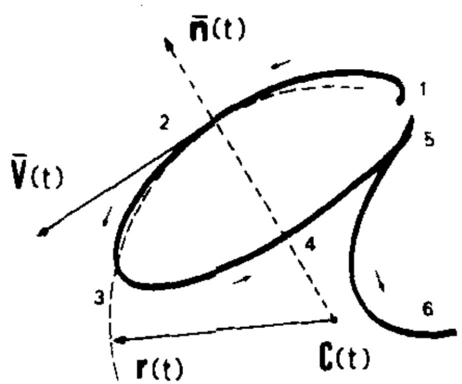


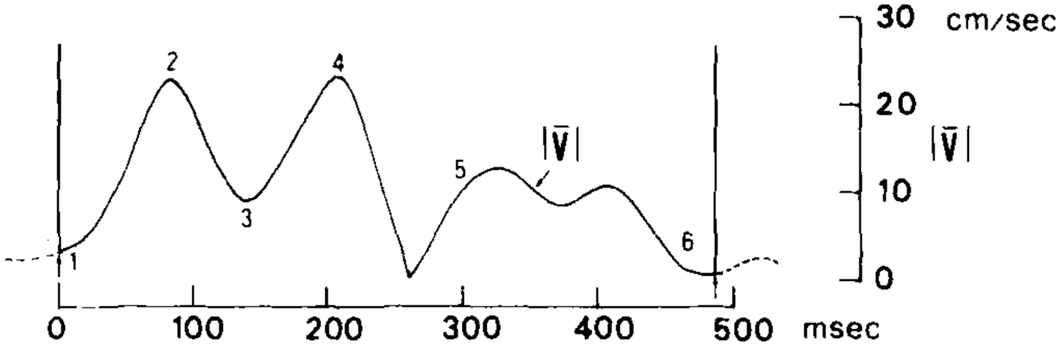
Viviani and McCollum 1983

*Tangential velocity

Kinematic regularity

- Velocity* (V) vs. curvature (C) obeys "power-law"





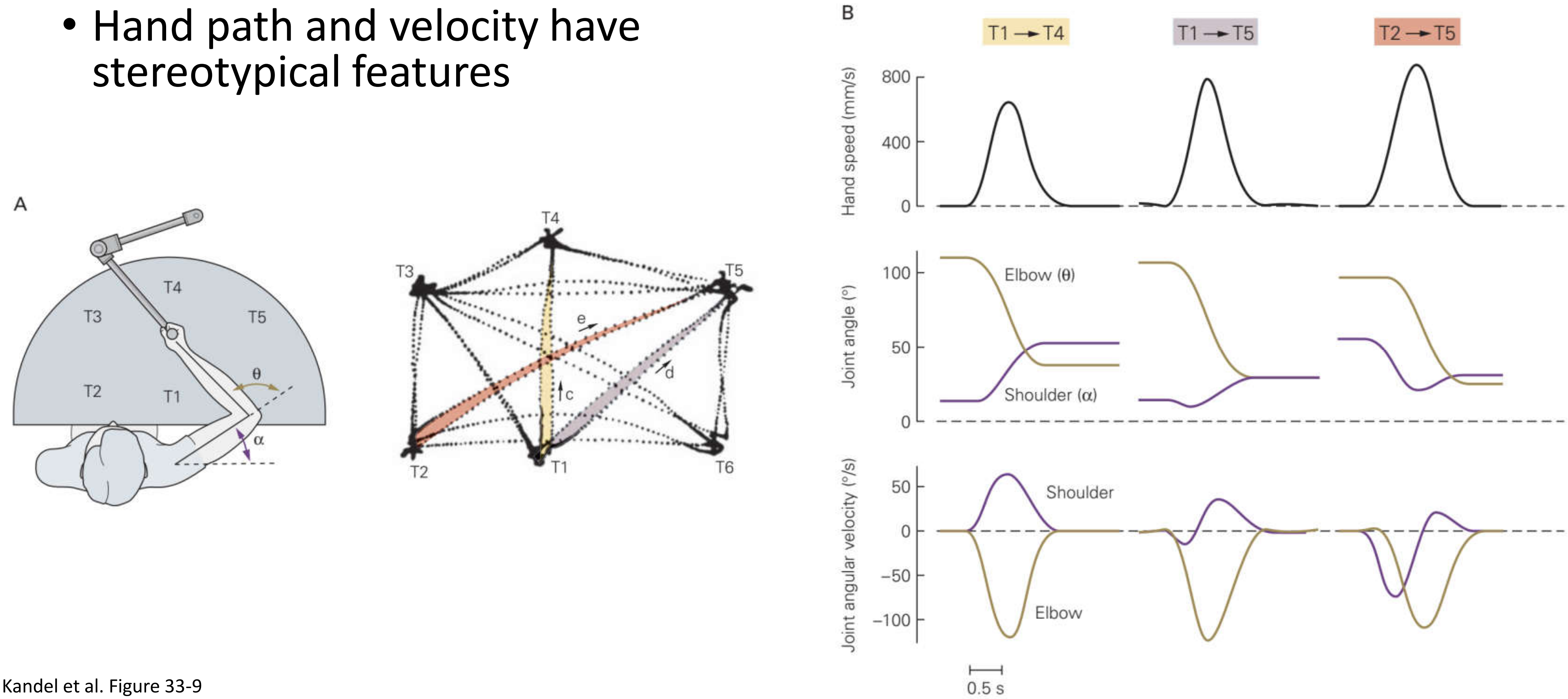
Viviani and Terzuolo 1980

- Smaller C (=1/R): larger V
- Points when movement direction is inverted: V goes to zero.

*Tangential velocity

Kinematic regularity

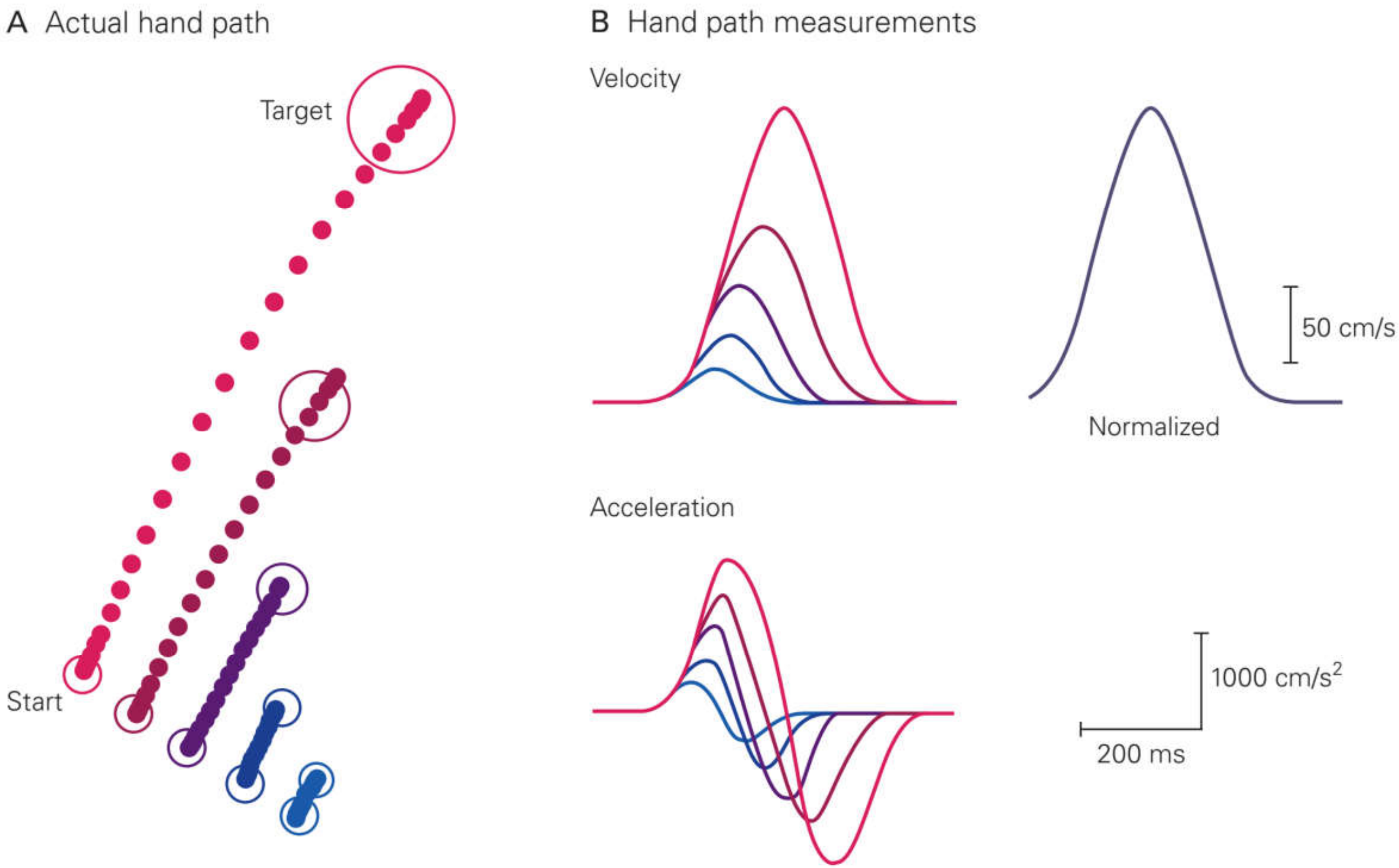
- Hand path and velocity have stereotypical features



Kandel et al. Figure 33-9

Kinematic regularity

- Velocity and acceleration as a function of distance



Kandel et al. Figure 33-12

Kinematic regularity

- Minimum jerk model

Smoothness can be quantified as a function of jerk, which is the time derivative of acceleration (Hogan 1984)

$$\text{jerk } \dddot{x}(t) = \frac{d^3x(t)}{dt^3}$$

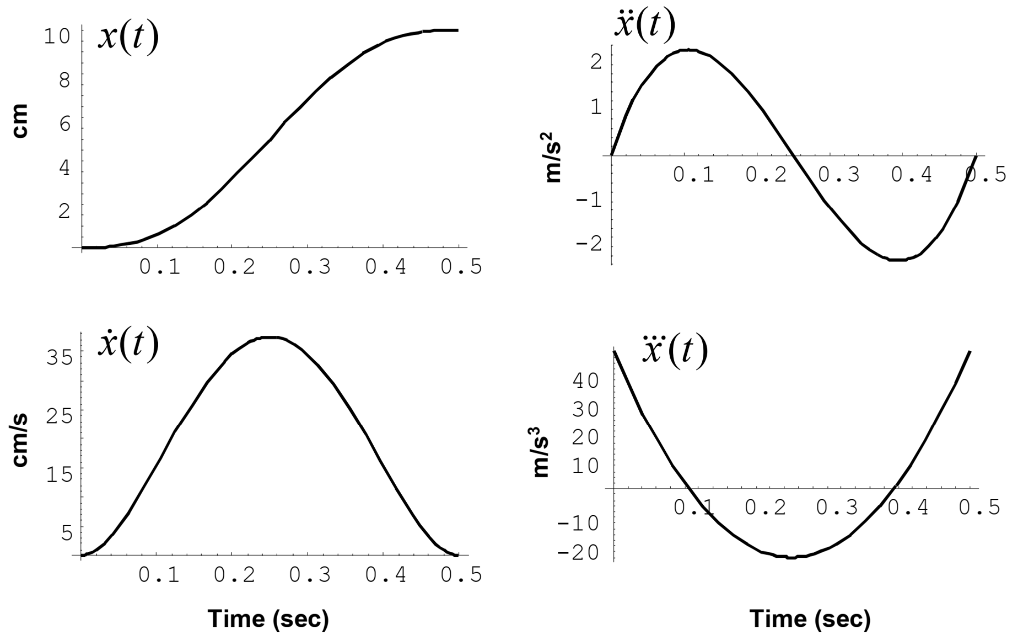
Minimum jerk cost

$$\int_{t=t_i}^{t_f} \dddot{x}_1(t)^2 \, dt$$

Solution: Minimum jerk trajectory

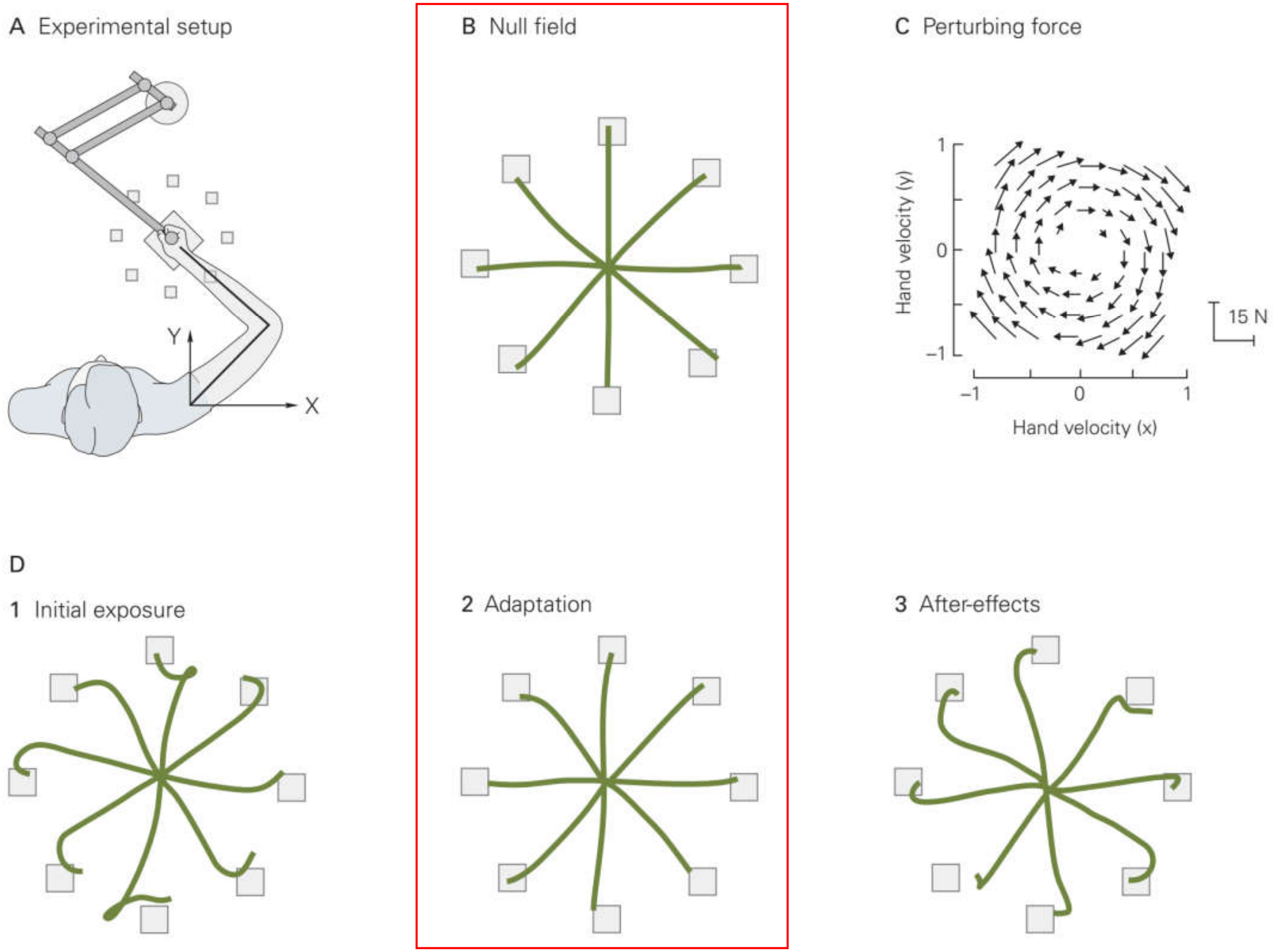
$$x(t) = x_i + (x_f - x_i)\left(10(t/d)^3 - 15(t/d)^4 + 6(t/d)^5\right)$$

i: initial; f: final; d: movement duration



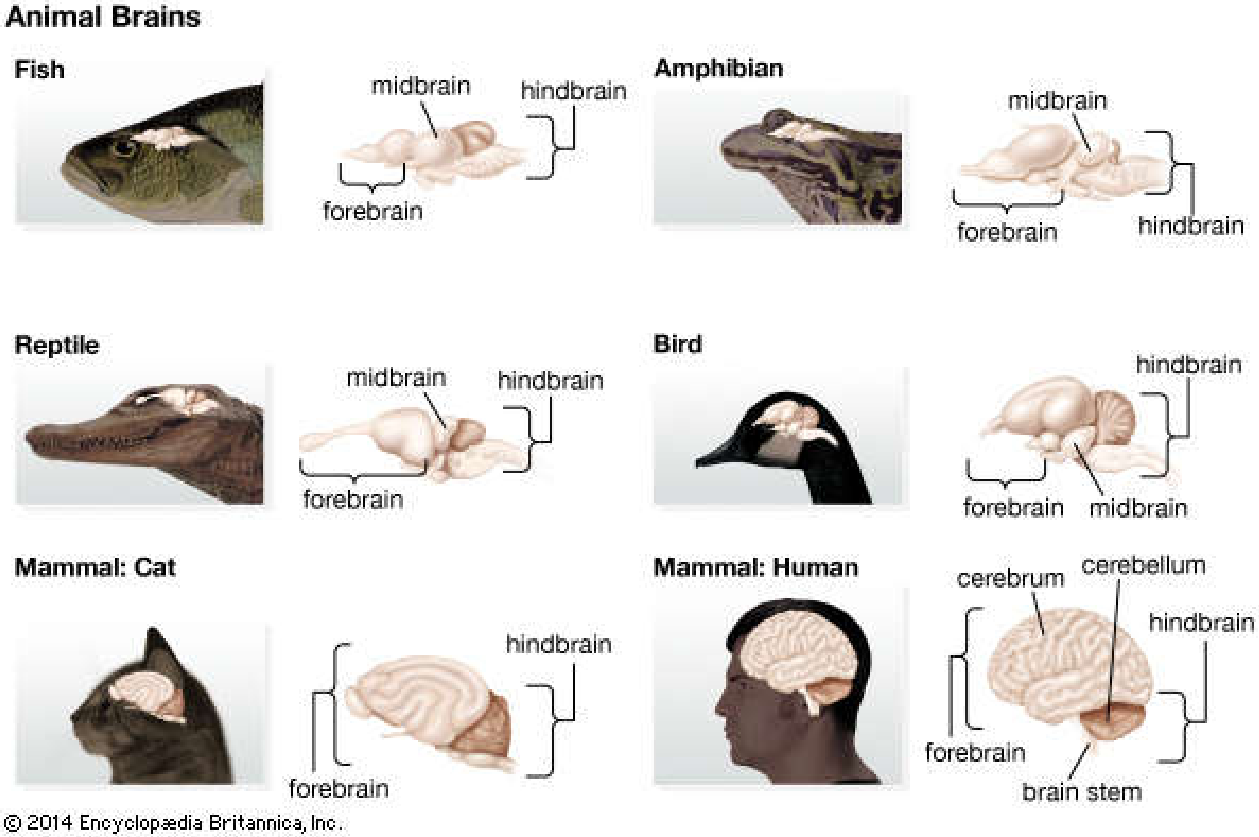
Complete derivation see: https://courses.shadmehrlab.org/Shortcourse/minimumjerk.pdf

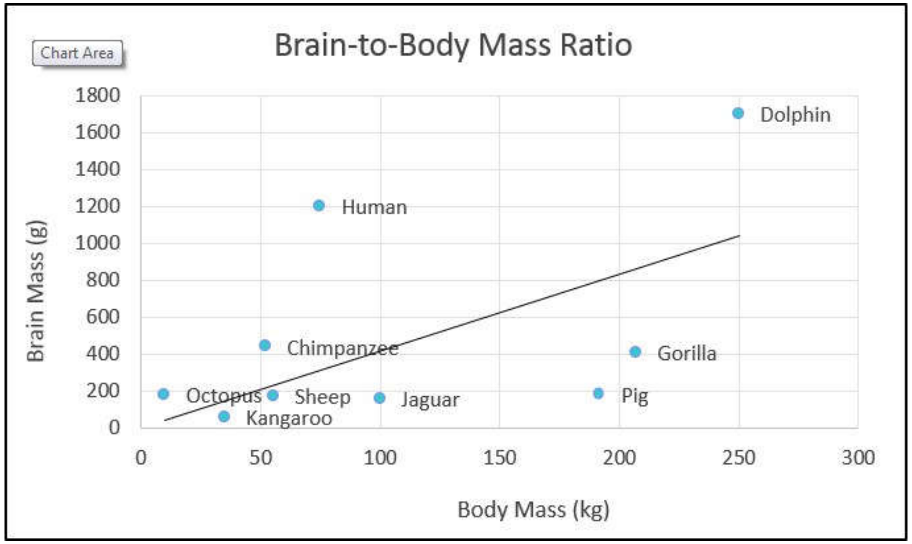
Kinematic regularity



Kandel et al. Figure 33-9

Comparison with animal brains

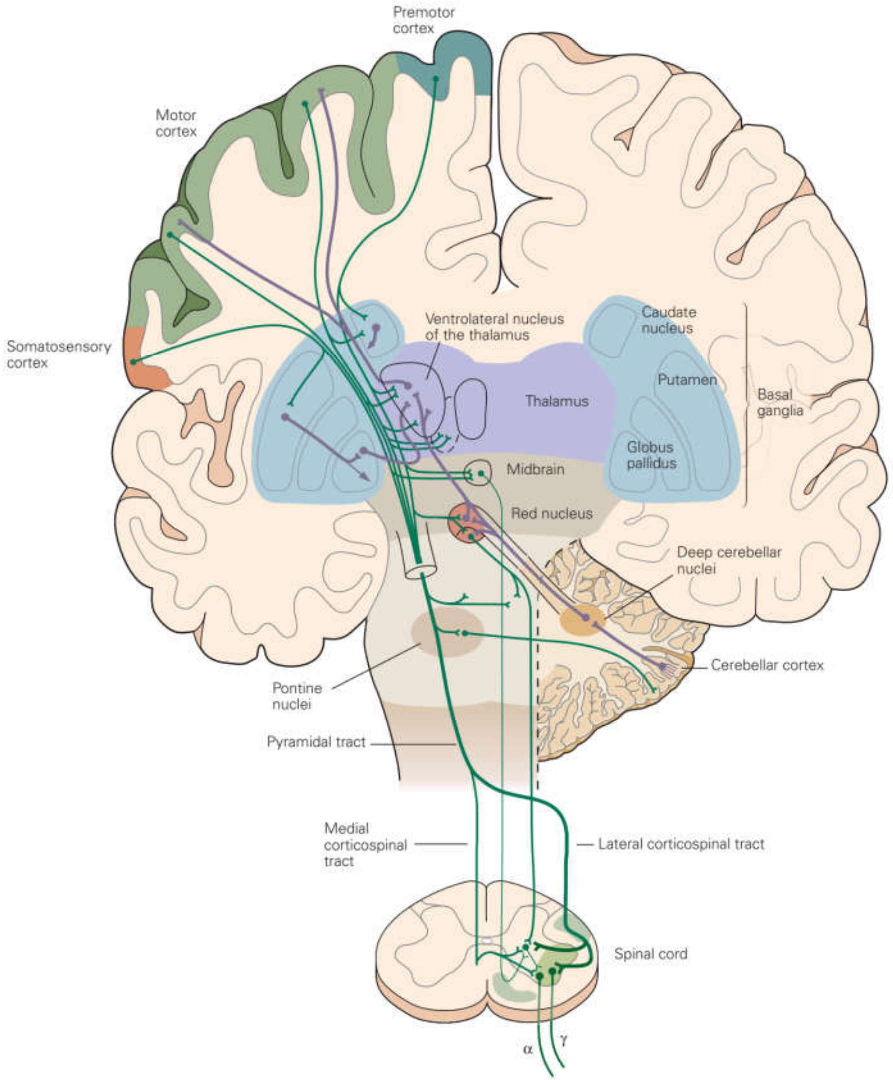


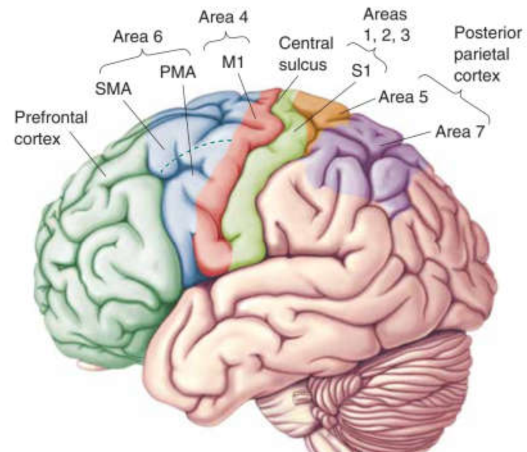


Brain circuits for movement generation

Overview

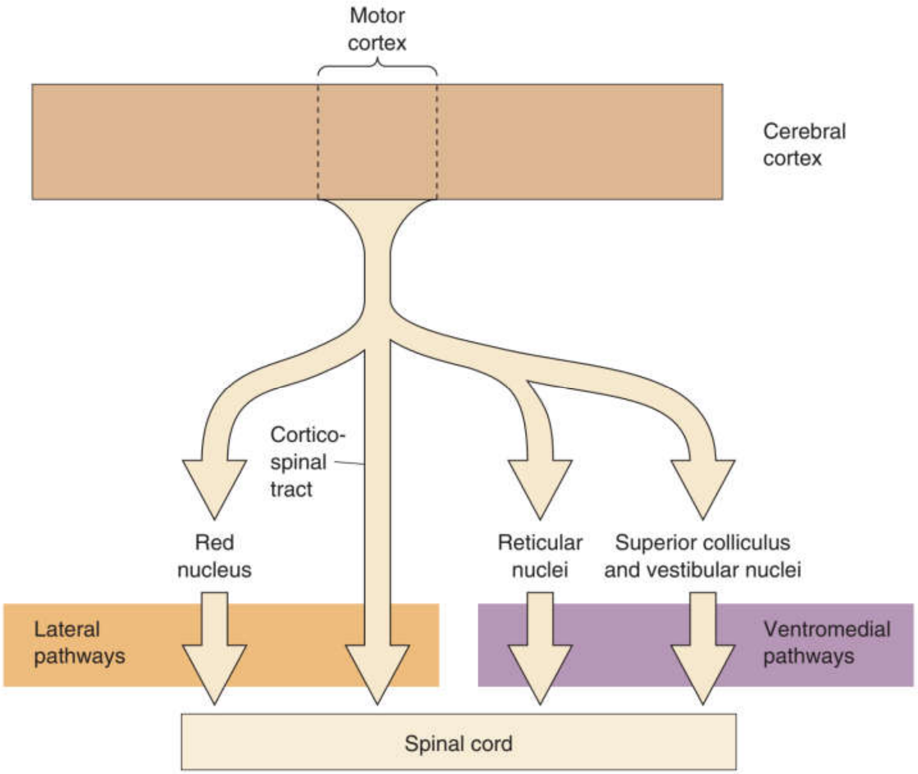
- Motor cortex
- Cerebellum
- Basal ganglia



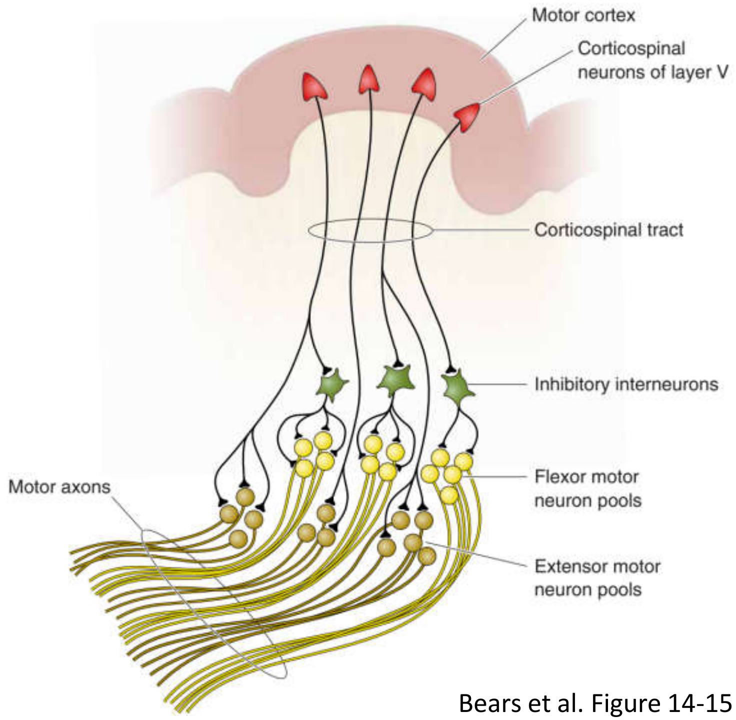


Kandel et al. Figure 14-7

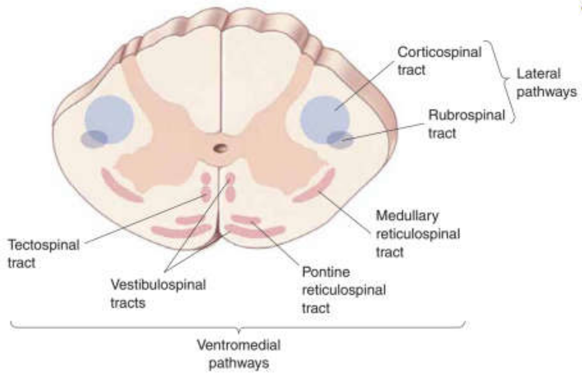
Motor Cortex – descending control of spinal cord



Bears et al. Figure 14-6

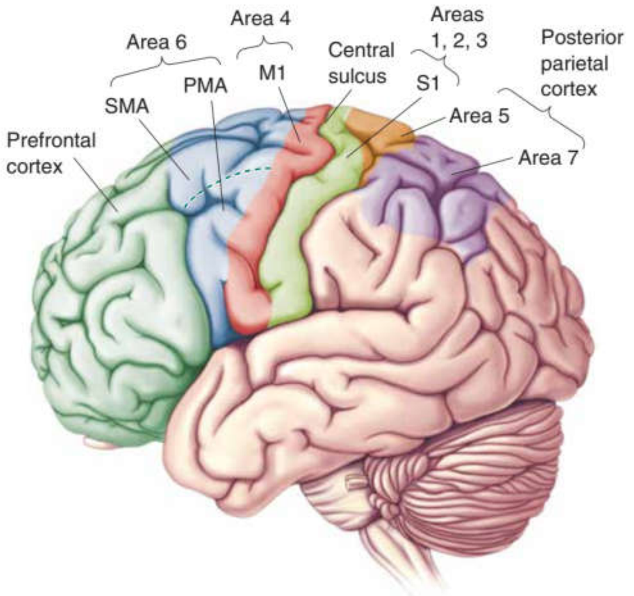


Bears et al. Figure 14-15

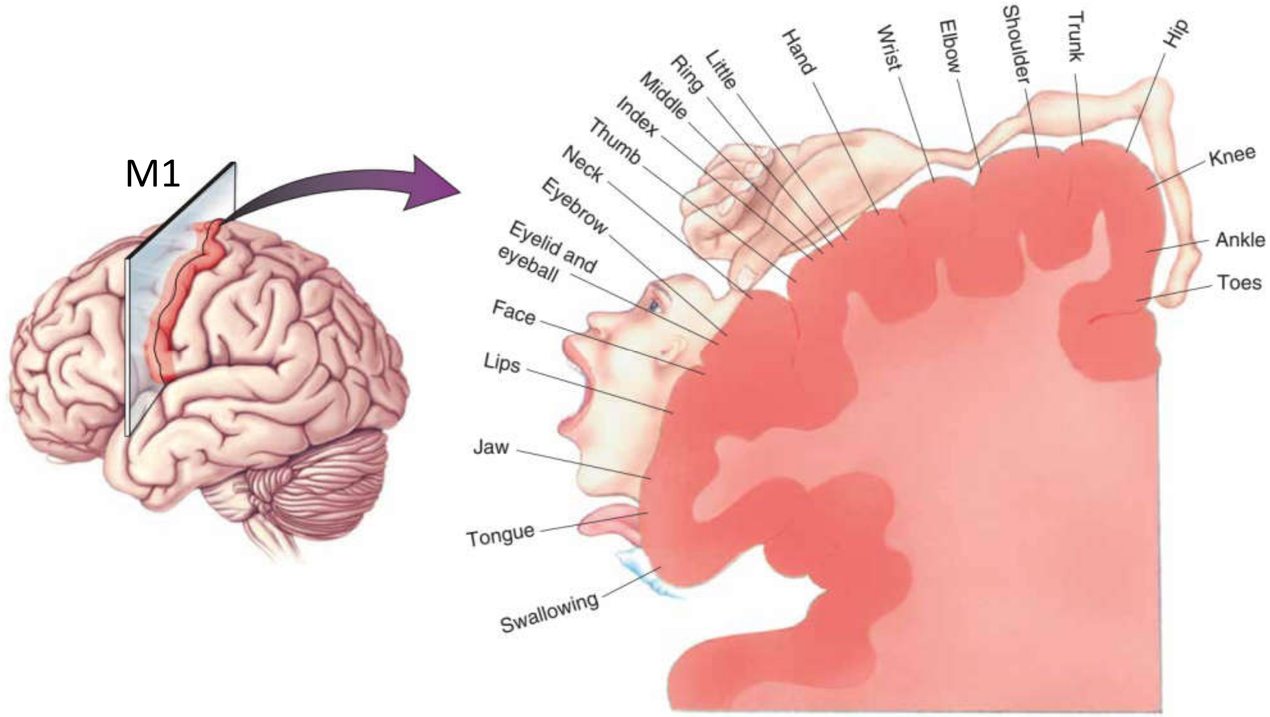


Motor Cortex:

- Primary cortex (M1)
- Premotor area (PMA)
- Supplementary motor area(SMA)

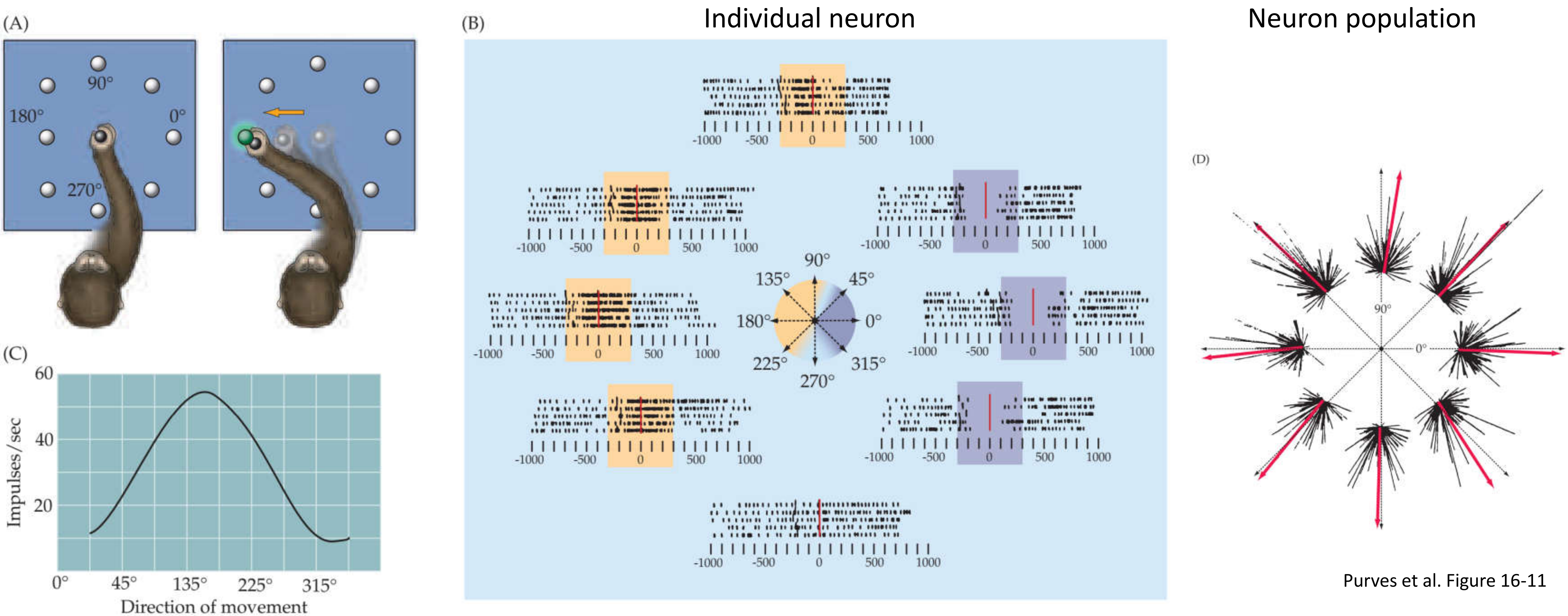


Bears et al. Figure 14-7



Bears et al. Figure 14-8

Primary cortex (M1) – population coding of movement direction

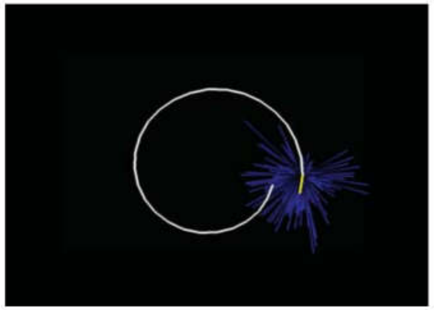


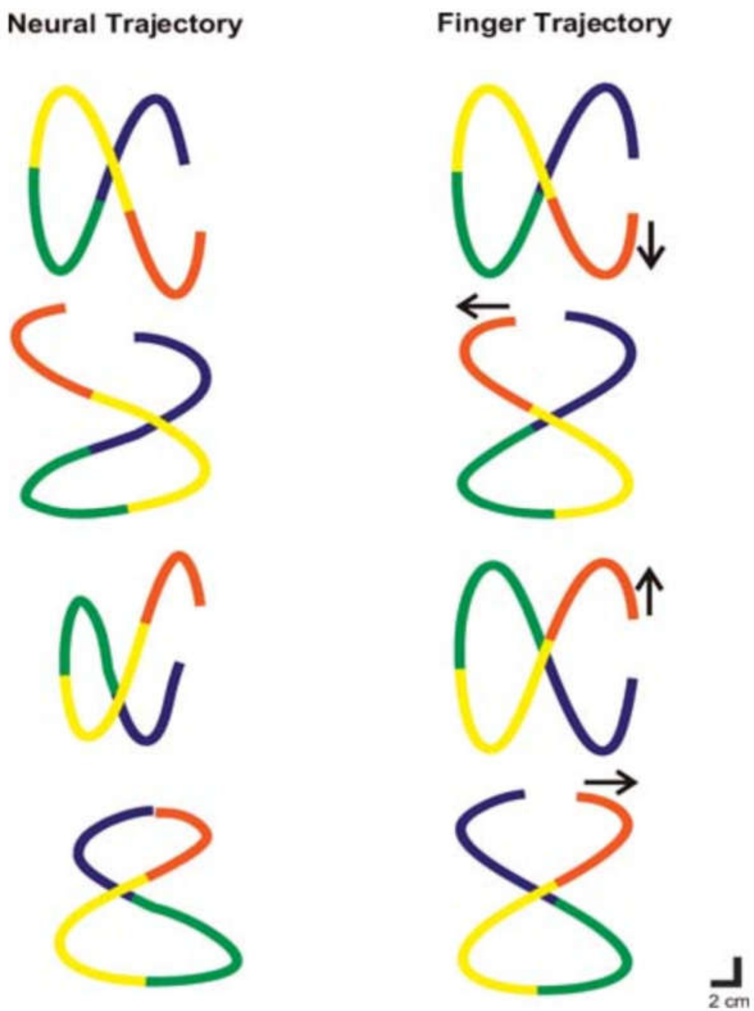
Purves et al. Figure 16-11

Individual M1 neuronal discharges cannot specify movement direction, because they are tuned too broadly;
Rather, each arm movement must be encoded by the concurrent discharges of a population of such neurons

Neural trajectory of M1 predicts motion

Neural trajectory is calculated from population vectors in time course



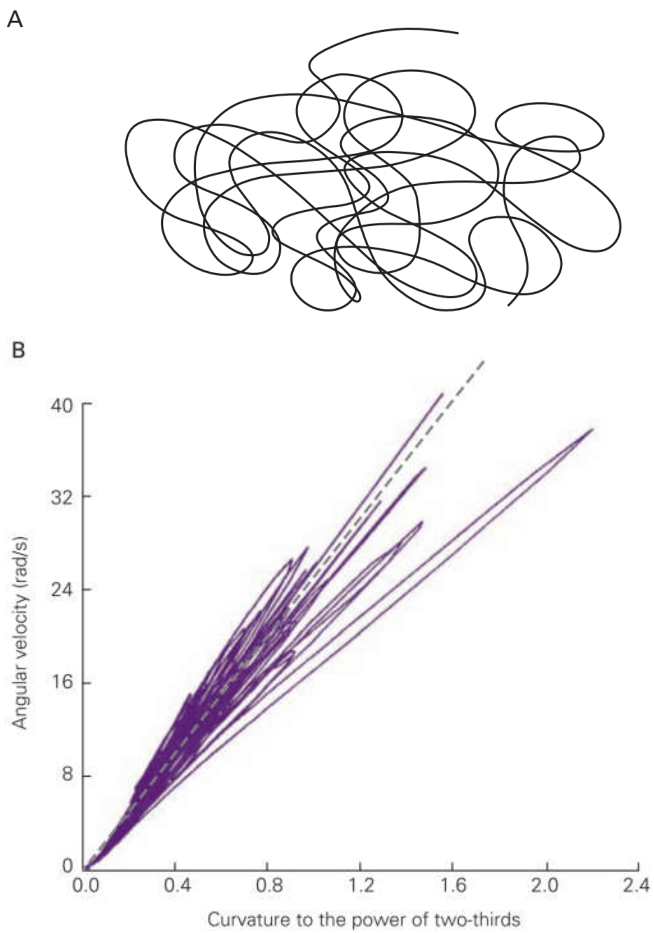


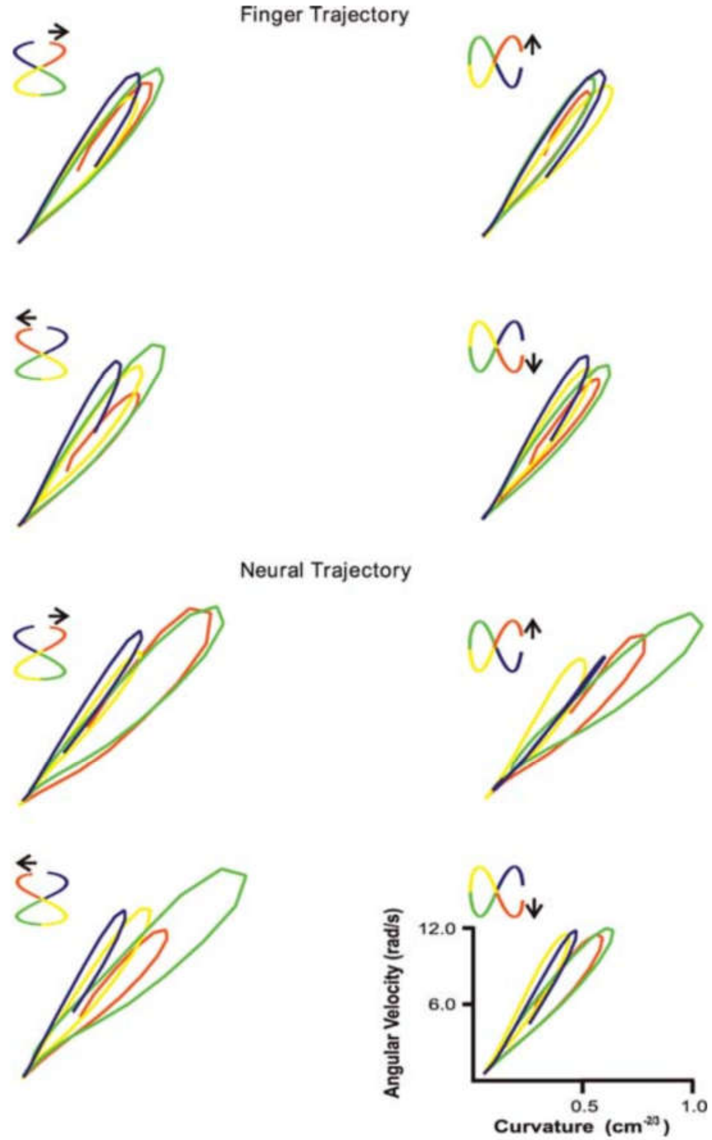
Segmentation during drawing

Schwartz J Physiol. 2007

Kinematic regularity – movement planning in M1?

- Velocity* vs. curvature obeys "power-law"





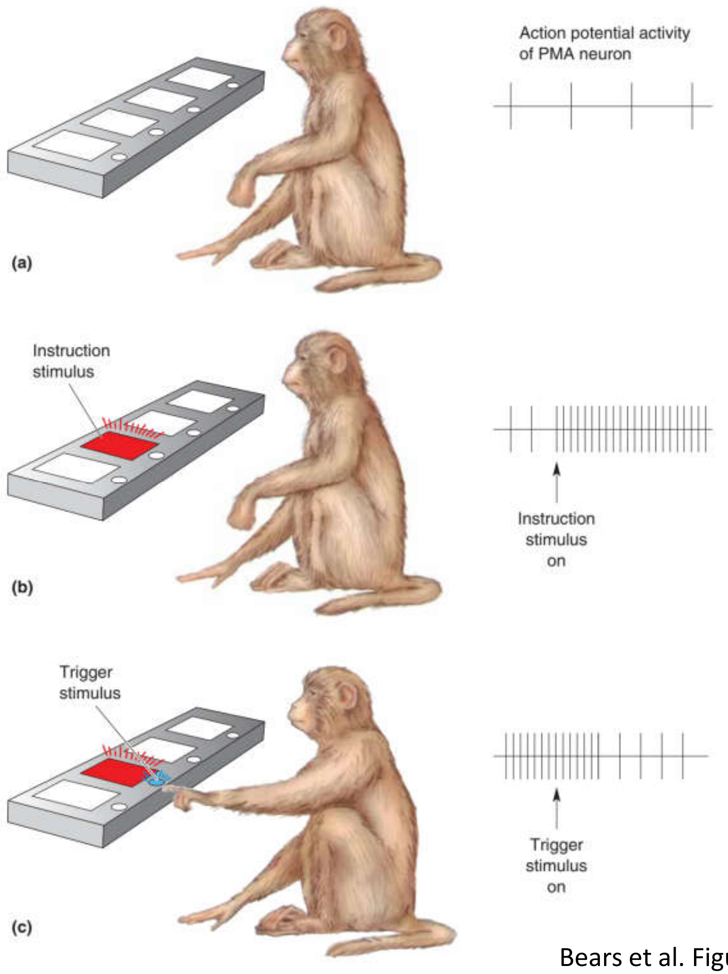
*Angular velocity

Kandel et al. Figure 33-8

Schwartz J Physiol. 2007

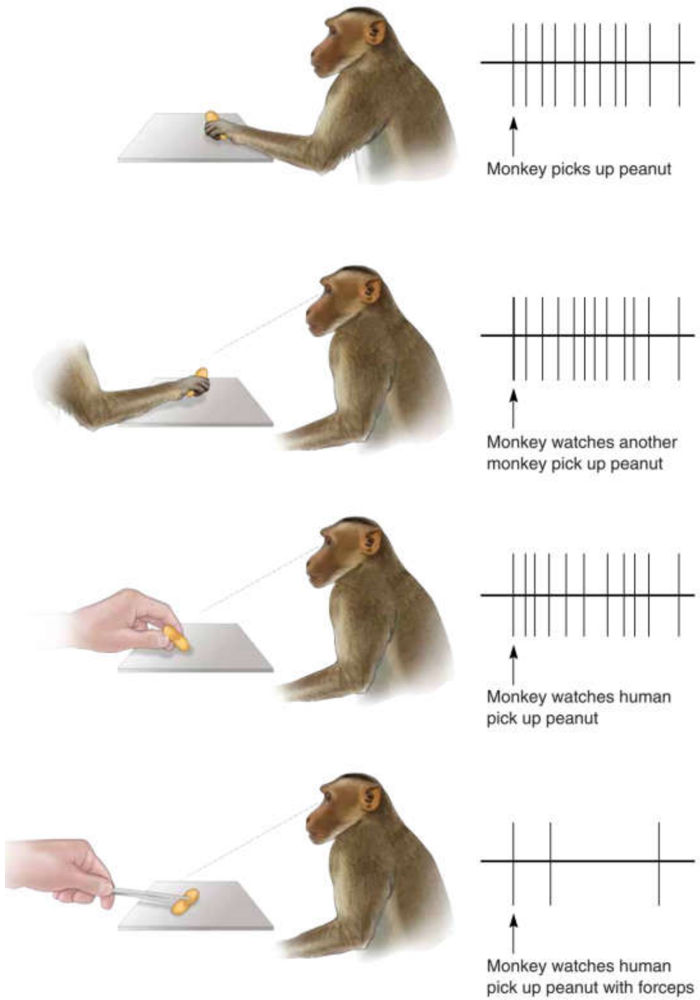
Premotor area (PMA)

Discharge of PMA neuron before a movement



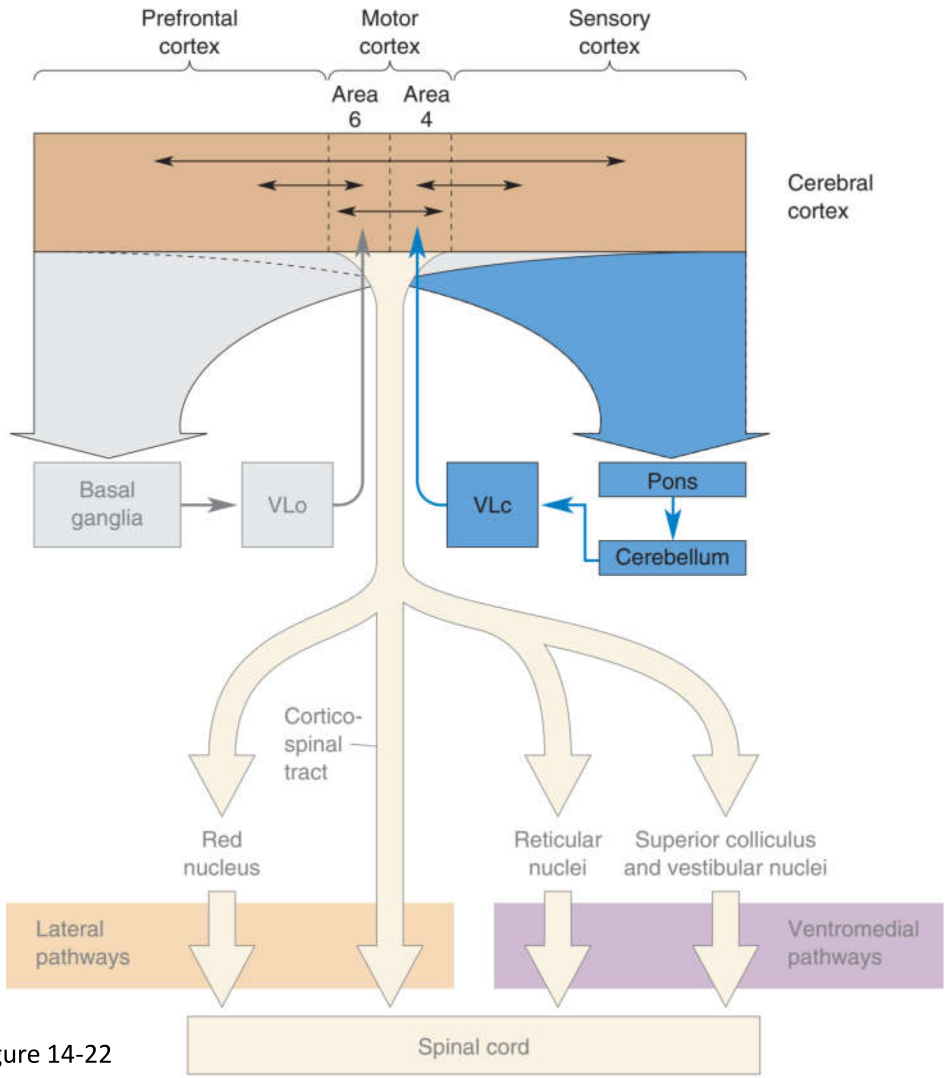
Bears et al. Figure 14-9

Discharge of a mirror neuron in PMA

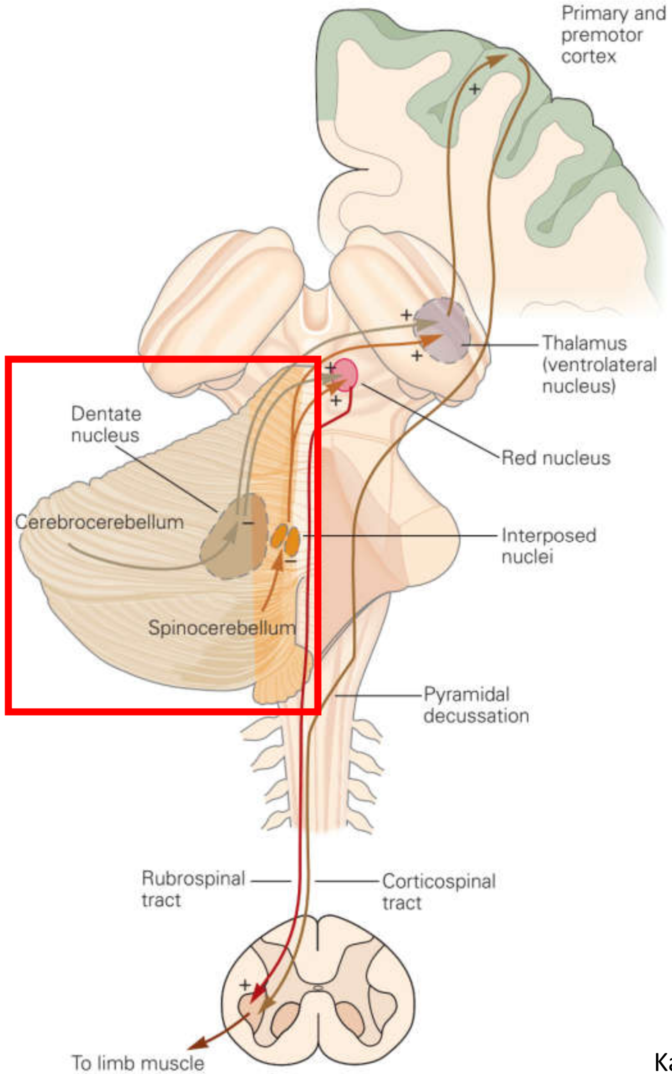


Bears et al. Figure 14-10

Cerebellum: coordination of movement



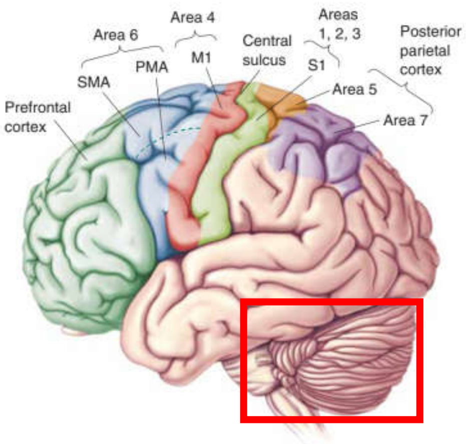
Bears et al. Figure 14-22



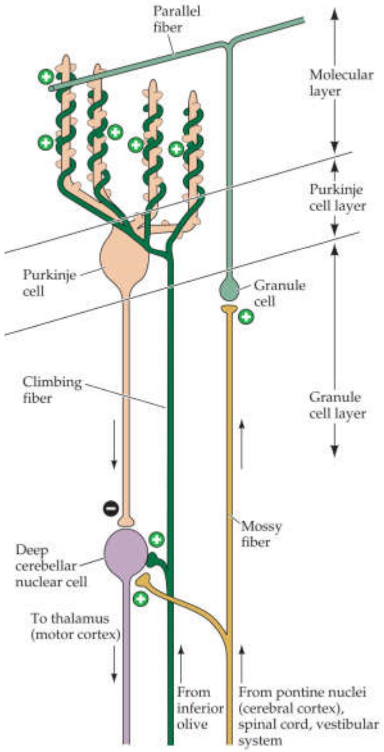
Kandel et al. Figure 42-7

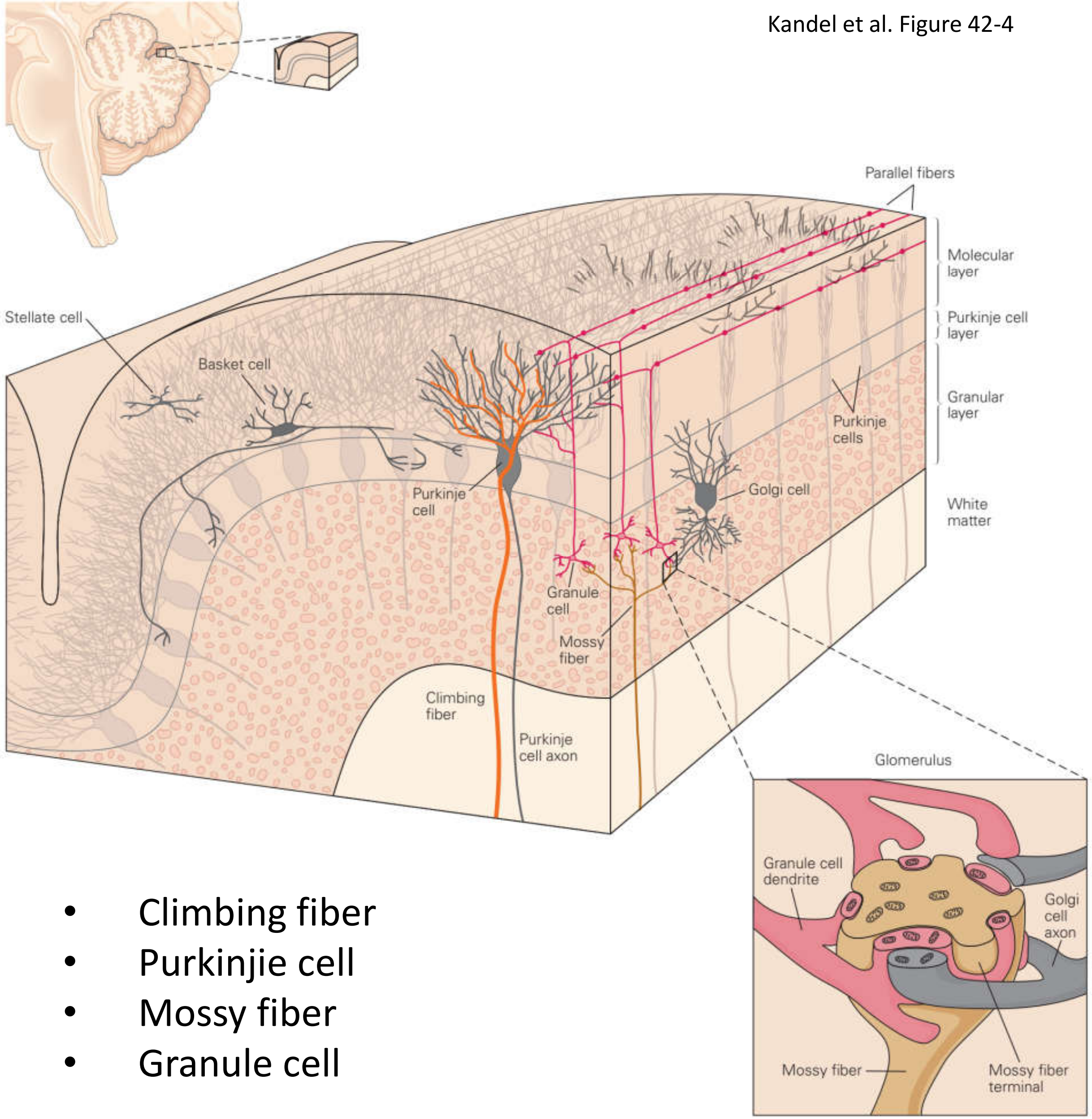
Cerebellum: anatomy

Kandel et al. Figure 42-4



Bears et al. Figure 14-7

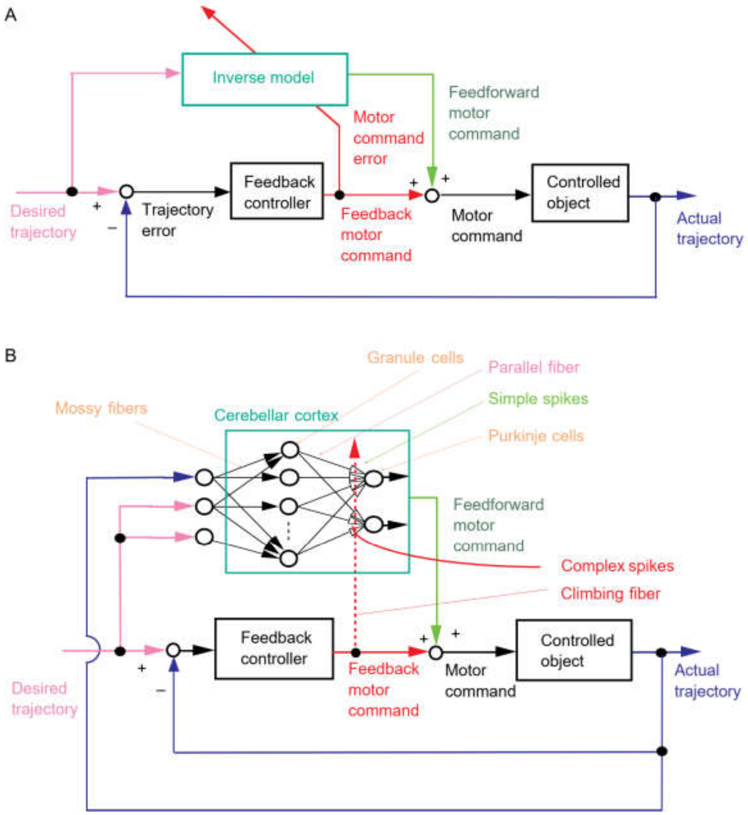




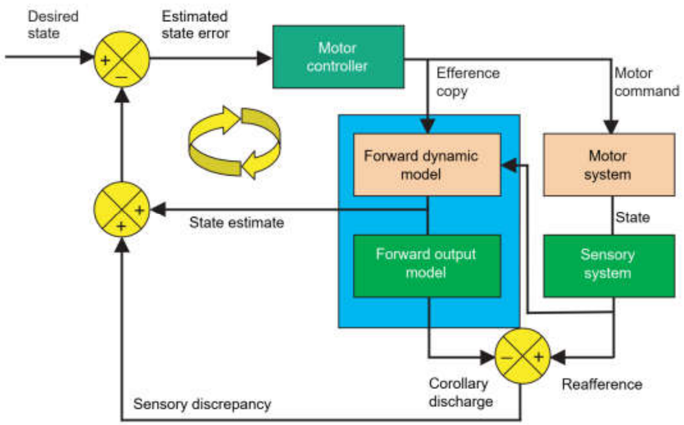
- Climbing fiber
- Purkinjie cell
- Mossy fiber
- Granule cell

Cerebellum - control model

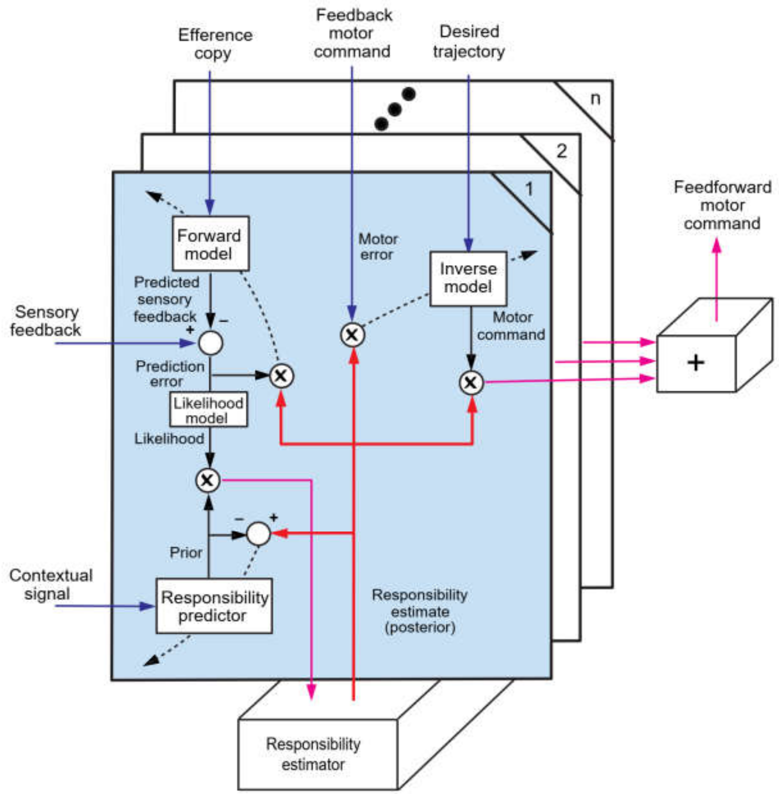
Inverse model (Feedback error-learning)



Forward model (Smith-predictor)

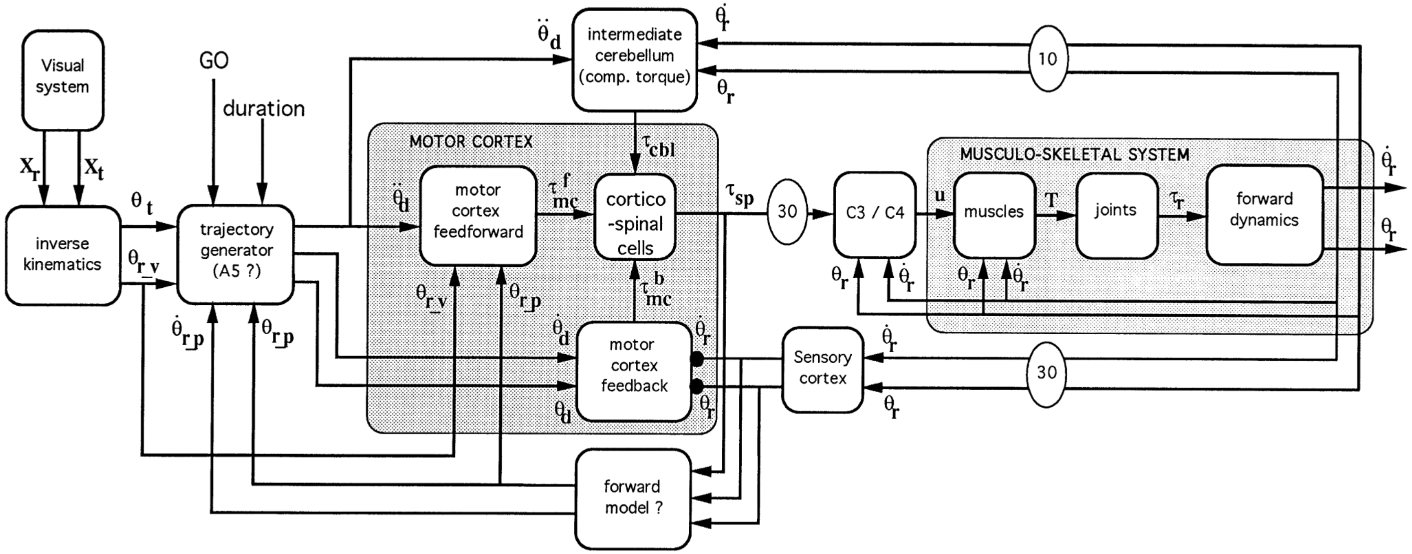


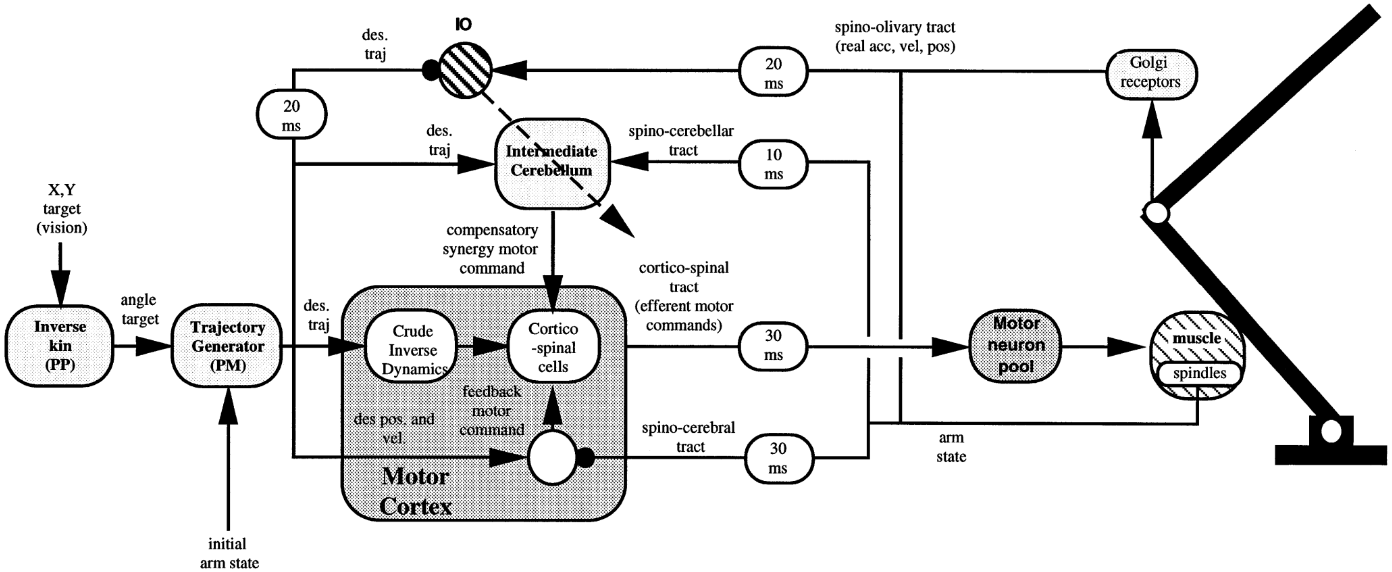
Multiple paired forward-inverse models



Wolpert et al. 1998

Cerebellar models for reaching movement

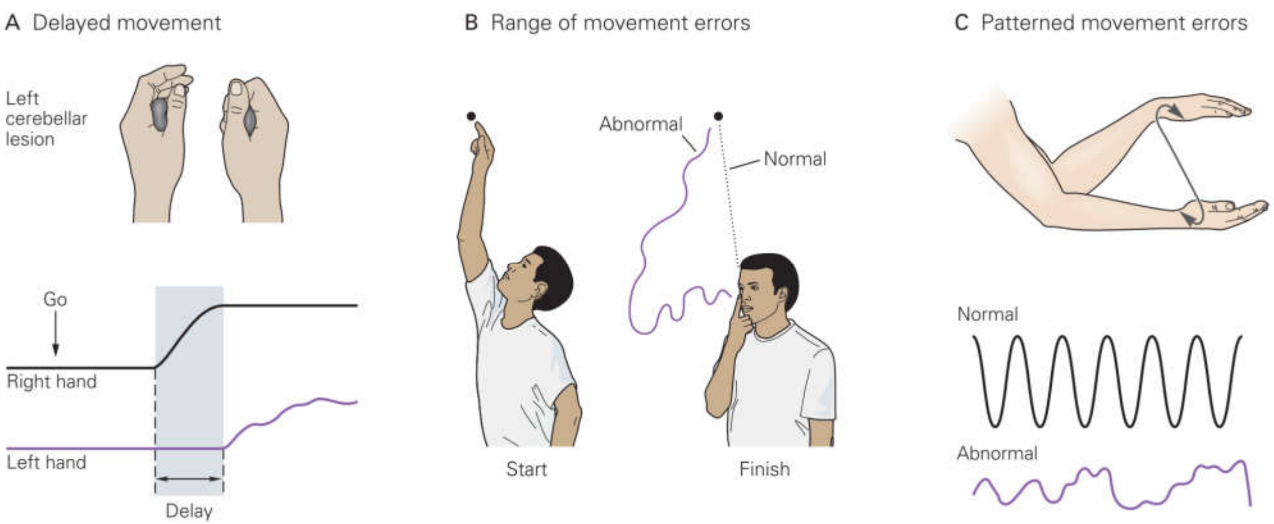


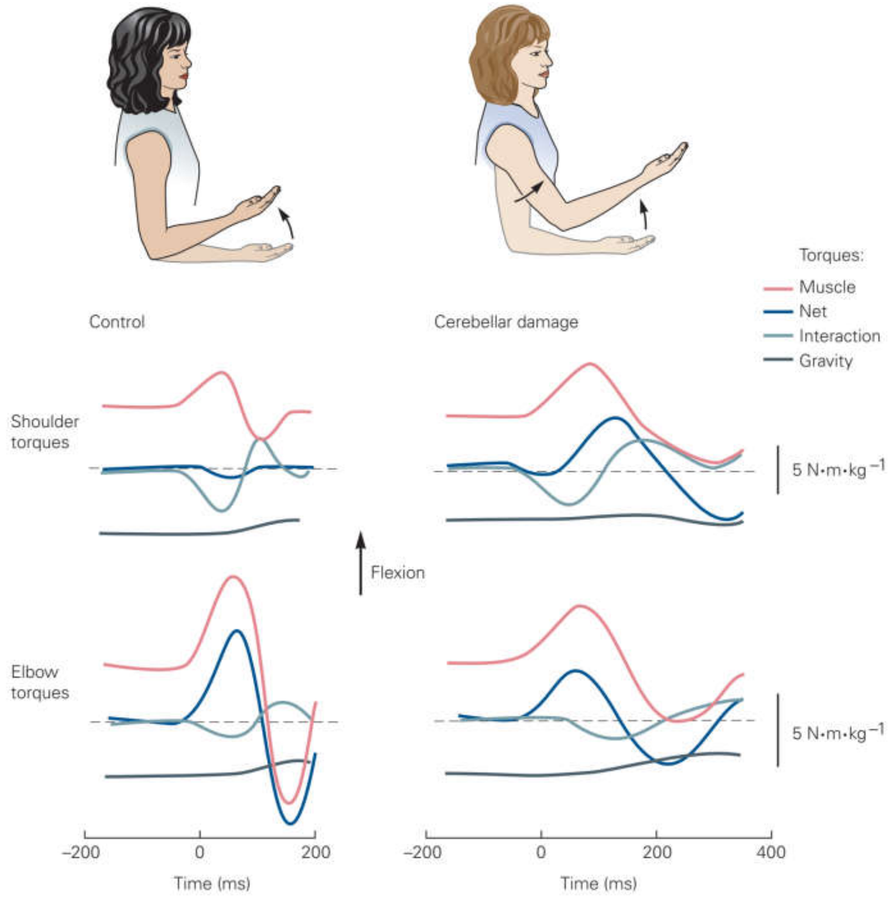


Schweighofer et al. 1998

Cerebellum: diseases

Deficits in coordination and timing

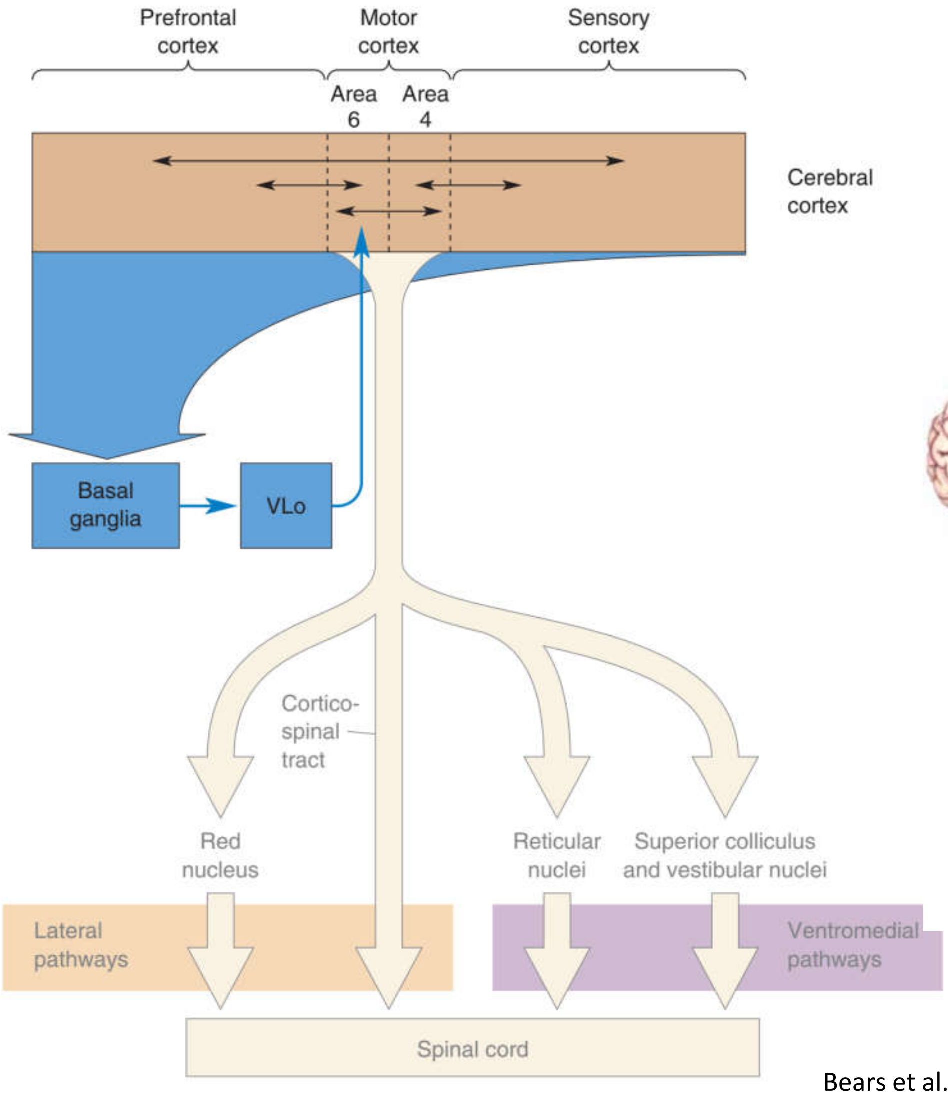




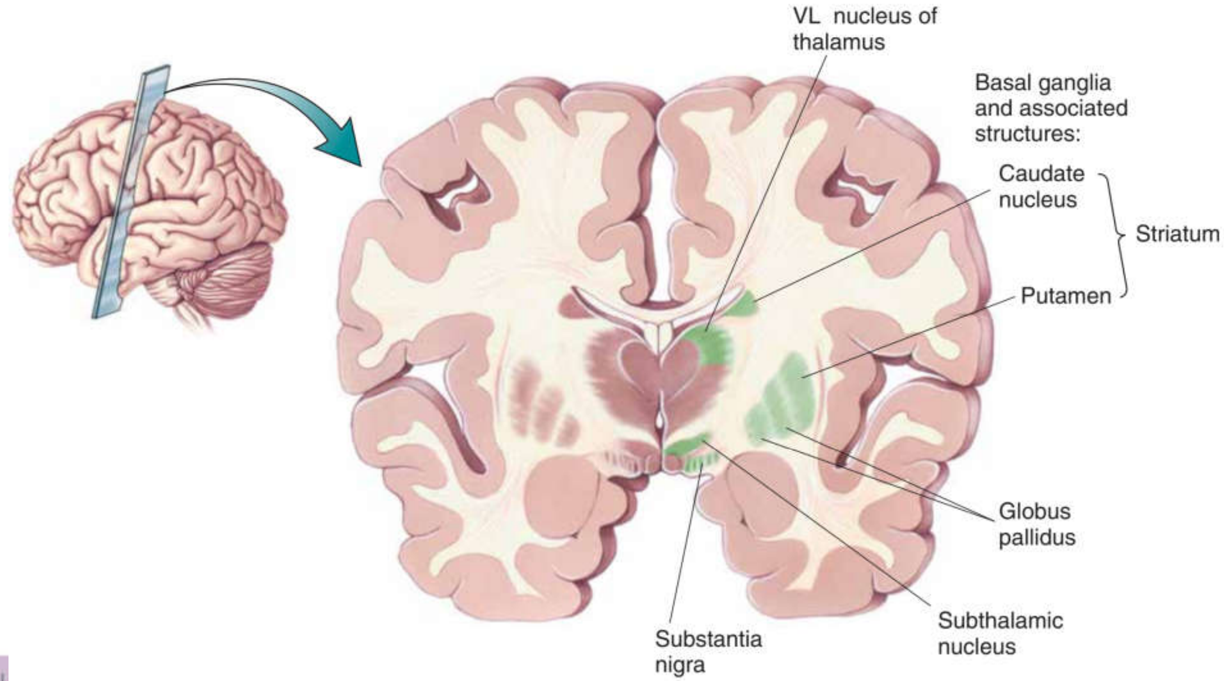
Kandel et al. Figure 42-1

Kandel et al. Figure 42-11

Basal ganglia: modulation of movement



Bears et al. Figure 14-11

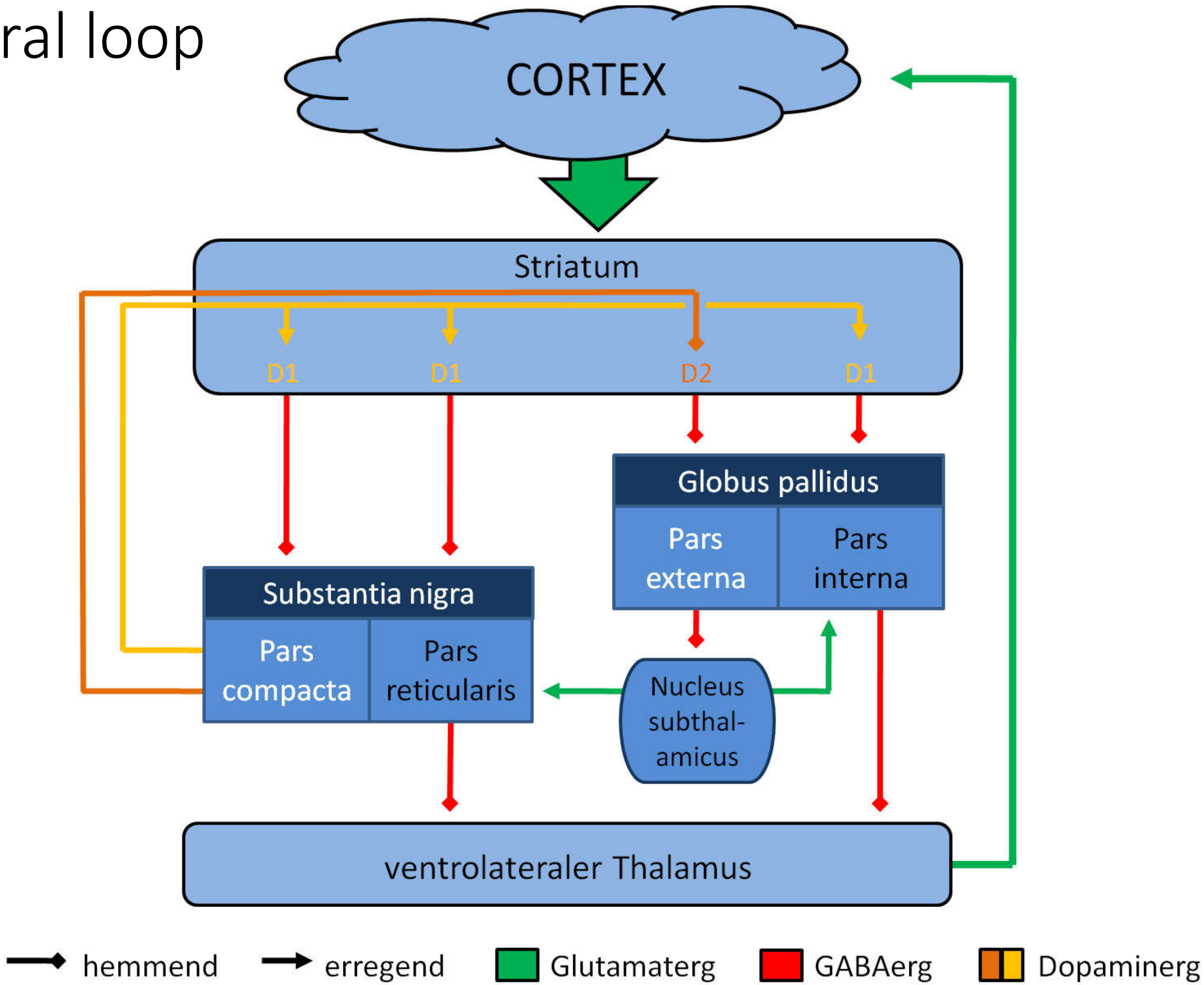


Bears et al. Figure 14-12

Basal ganglia: neural loop

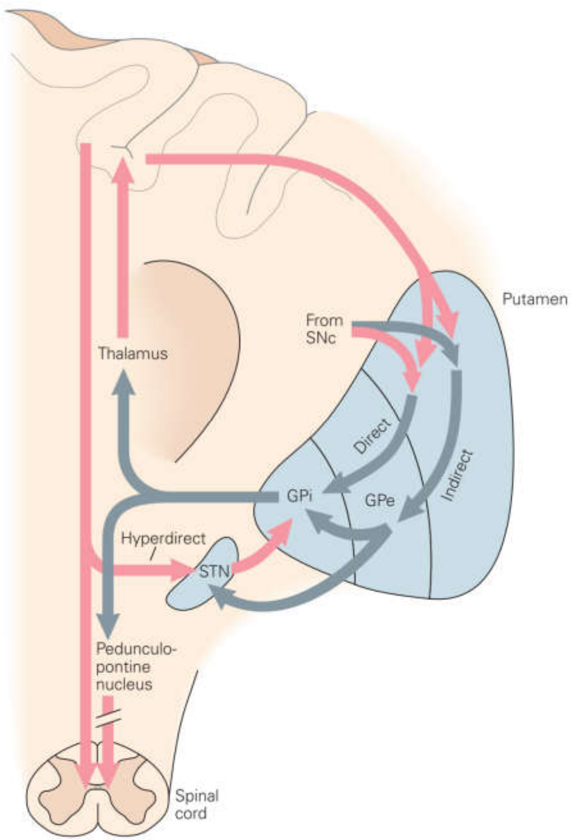
Neurotransmitters:
- Glutamate (+)
- GABA (-)
- Dopamine (+/-)

Dopamine receptor:
- D1 (+)
- D2 (-)

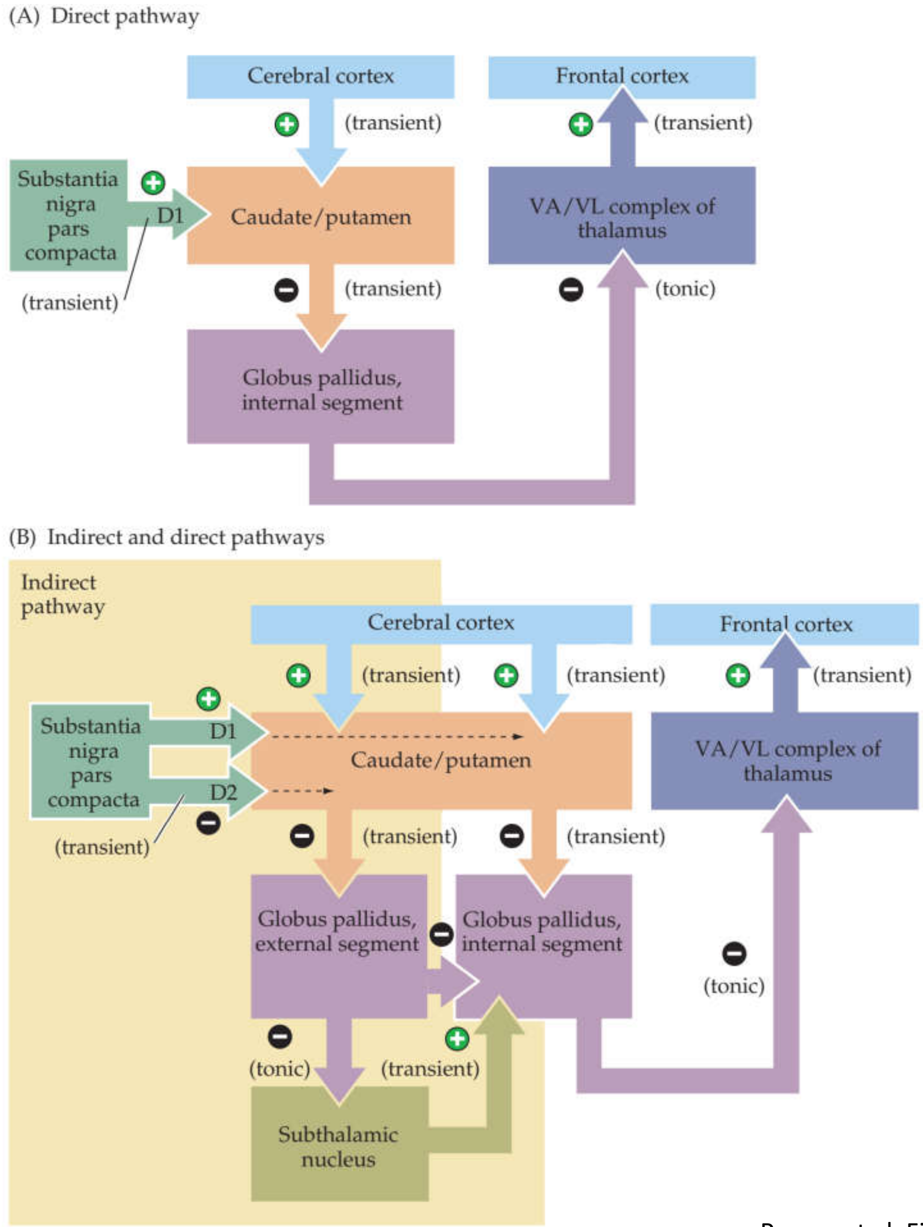


https://de.wikipedia.org/wiki/Basalganglien

Basal ganglia: neural loop



Kandel et al. Figure 43-2



Purves et al. Figure 17-8

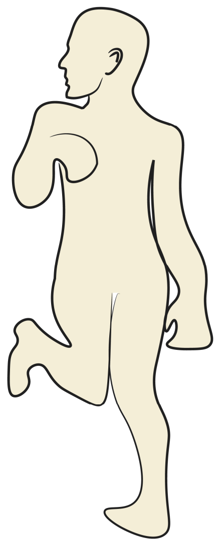
Basal ganglia: diseases

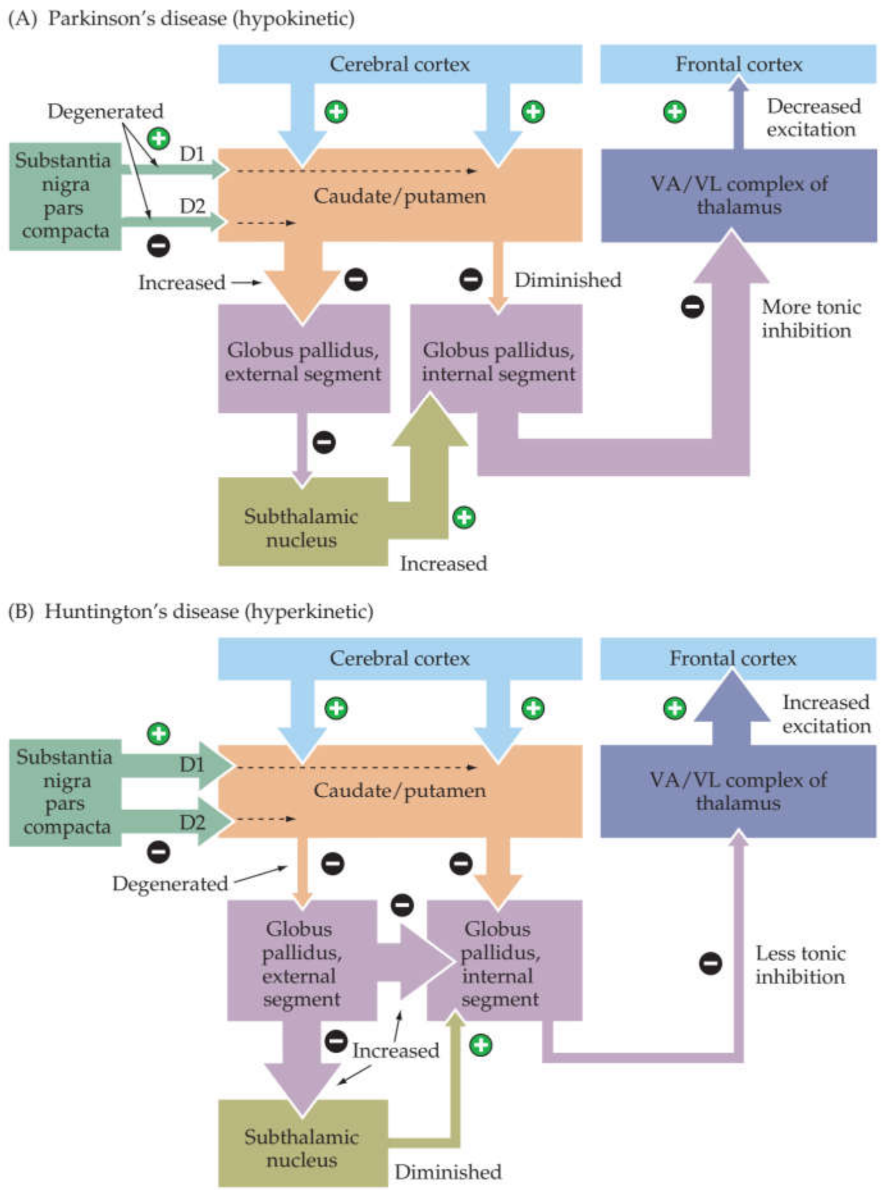
Parkinson‘s disease

- Resting tremor
- Rigidity/Freezing
- No tremor when moving
- Cause: loss of dopaminergic neurons
- Why such neurons die is unknown

Huntington‘s disease

- Chorea (dance)
- Involuntary but coordinated
- Cause: gene mutation





Purves et al. Figure 17-10

Summary and questions

Kinematic regularity:

- Speed-accuracy trade-off – Fitt's law
- Velocity vs. curvature - power law
- Bell-shaped hand velocity – minimum jerk model
- Force field adaptation

Brain control of movement:

- Motor cortex involves in the planning, control, and execution of voluntary movements
- Cerebellum coordinates voluntary movements
- Basal ganglia strongly interconnects with several brain regions for movement production