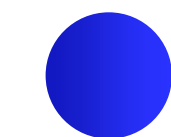
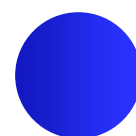


# SCUBALANCE

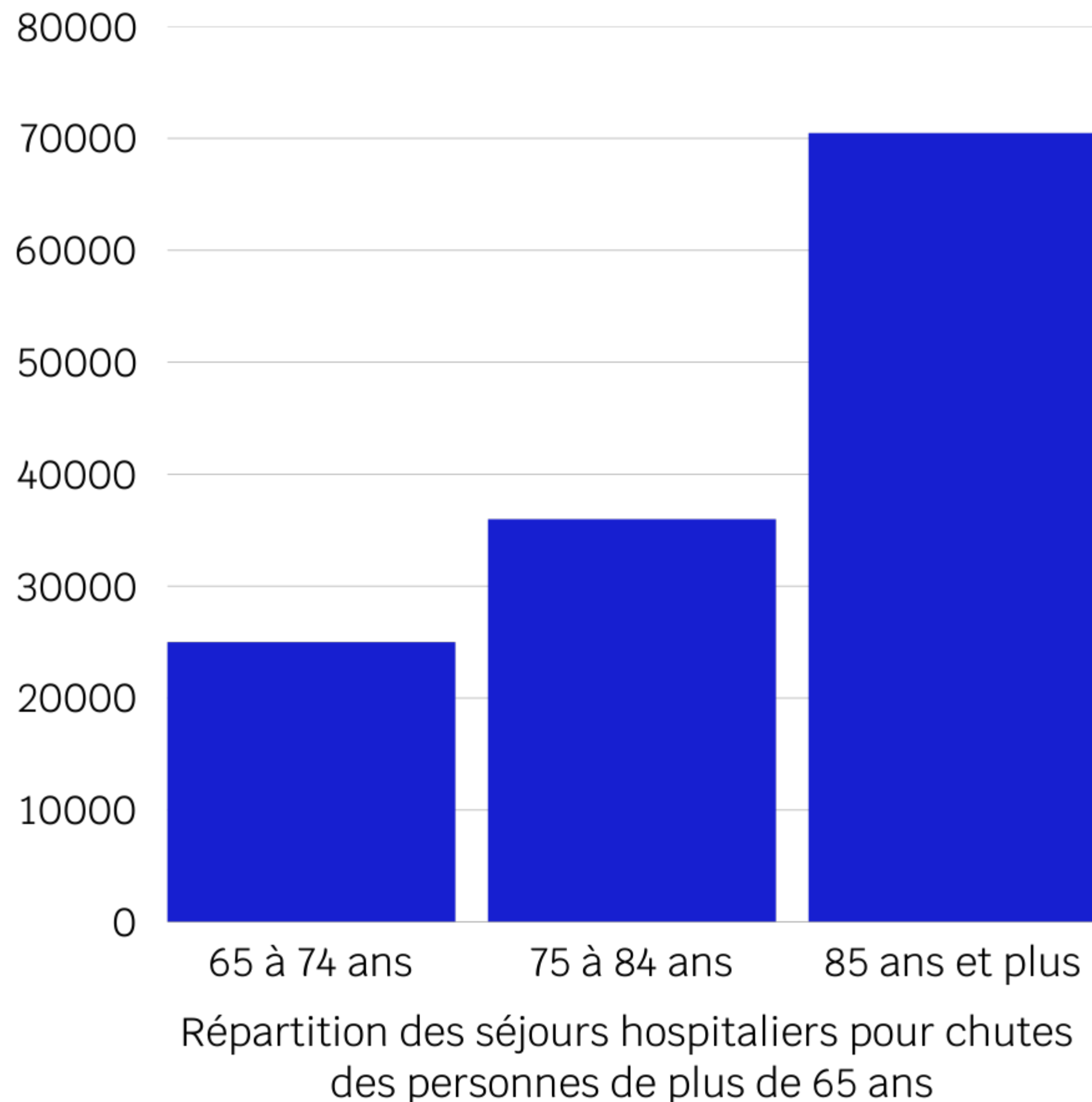
**Optimisation de stimuli visuels induisant  
des réponses posturales en  
environnement virtuel**

B.Toussaint-Malard, P.Laguillaumie,  
A.Decatoire, A.Marchand-Arnold,  
M.Billot, F.Danion, R.Tisserand



**05/06/25**

# Enjeu de santé publique et politique



**Axe 1 : Repérer les risques de chute et alerter**

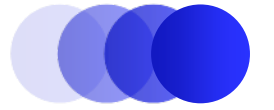
**Axe 2 : Aménager son logement pour éviter les risques de chute**

**Axe 3 : Des aides techniques pour la mobilité faites pour tous**

**Axe 4 : L'activité physique, meilleure arme antichute**

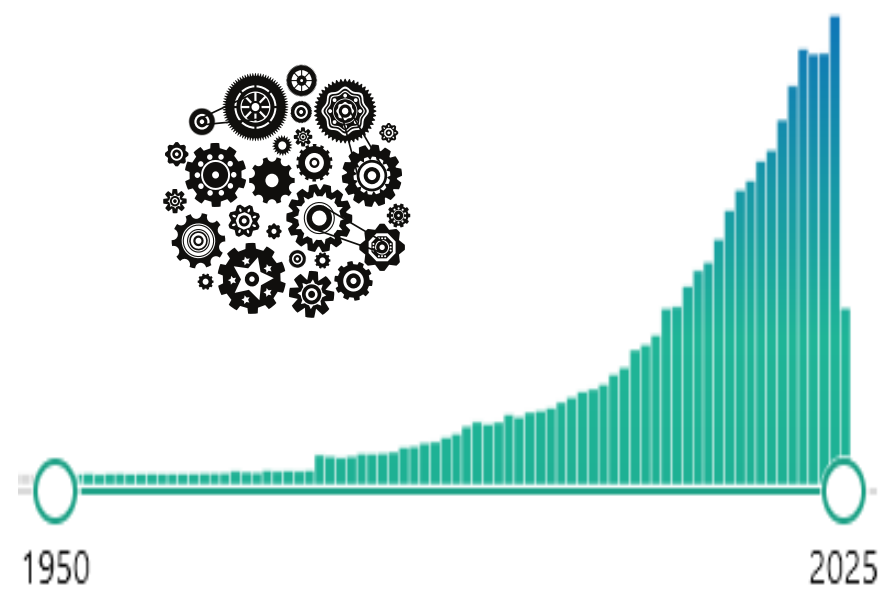
**Axe 5 : La téléassistance pour tous**

# Axe 1 : Repérer les risques de chute et alerter

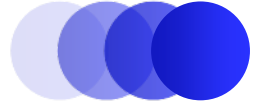


Degré de priorité élevé aux travaux de recherche sur les chutes et en mettant en place des mesures efficaces pour réduire les risques

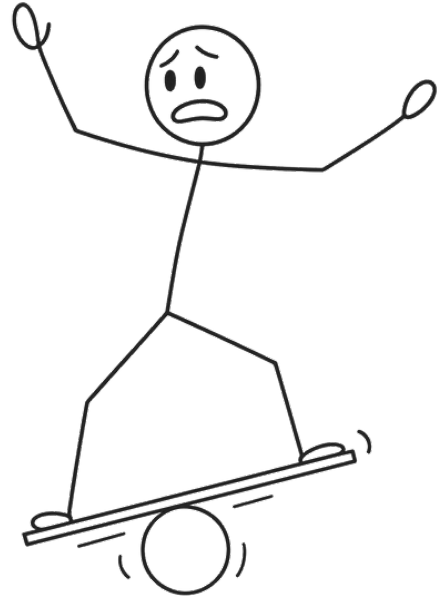
Comprendre les mécanismes liés à la chute



# Axe 1 : Repérer les risques de chute et alerter



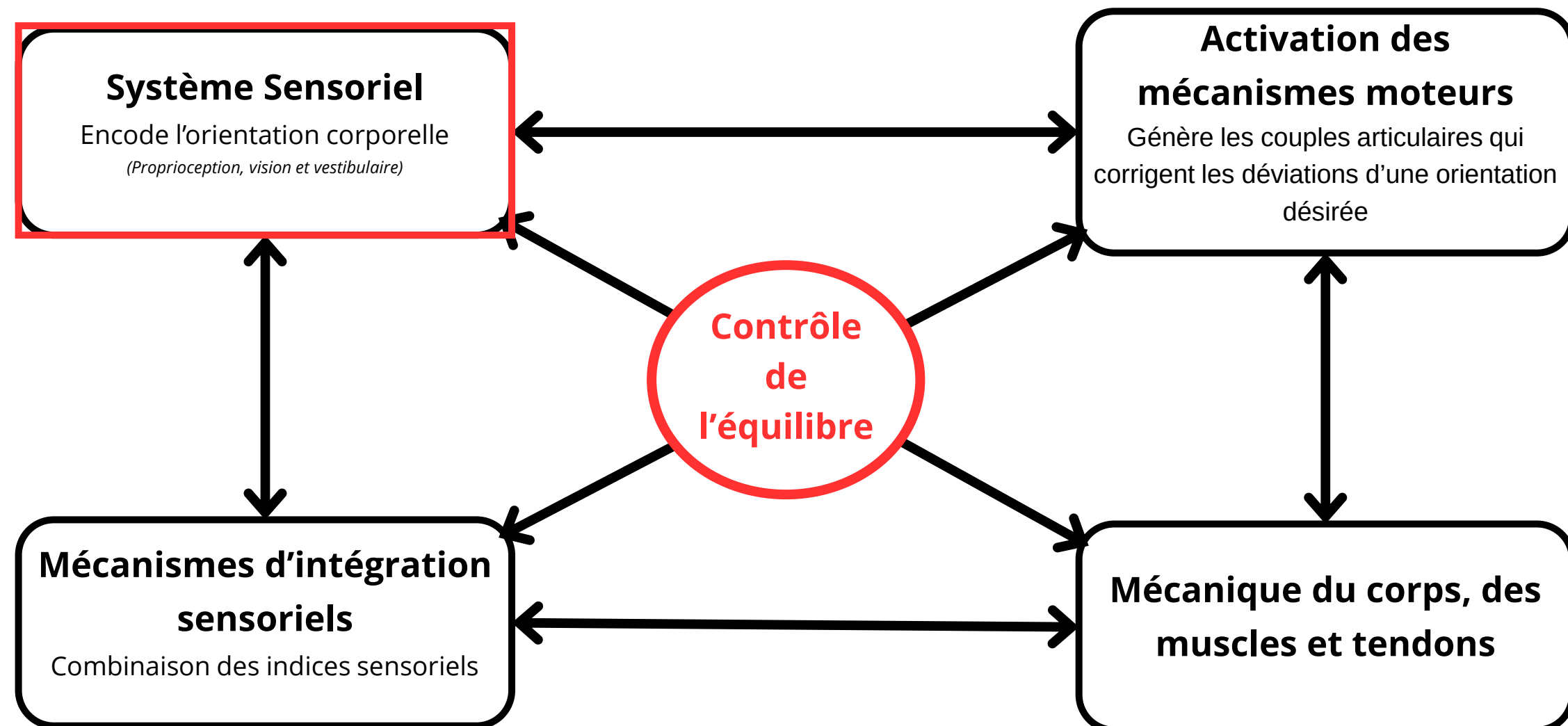
Hof, Gazendam et Sinke, 2004



Deux conditions :

- **“Statique”** : Projection verticale du Centre de Masse (CoM) se situe dans la base de support (BoS)
- **“Dynamique”** : Si CoM ne se situe pas dans la BoS mais que la vitesse est dirigée vers celle-ci, l'équilibre peut-être atteint

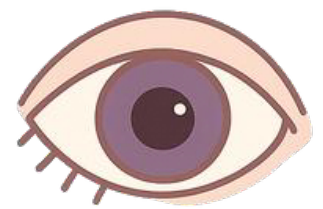
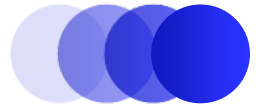
Le contrôle de l'équilibre est organisé selon :  
**“closed-loop feedback-control system”**



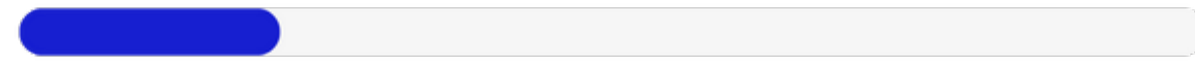
Peterka, 2002

# Implementation of a Central Sensorimotor Integration Test for Characterization of Human Balance Control During Stance

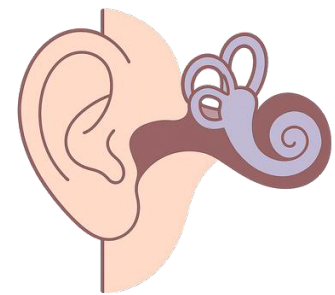
Peterka et al., 2018



**Système Visuel**



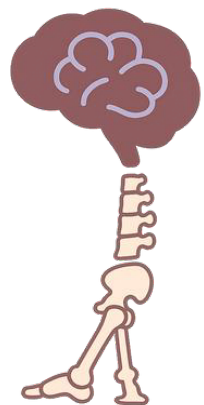
22%



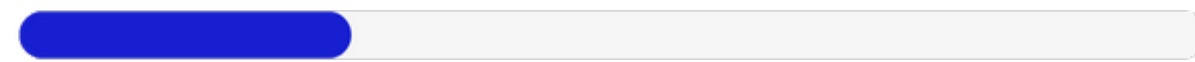
**Système Vestibulaire**



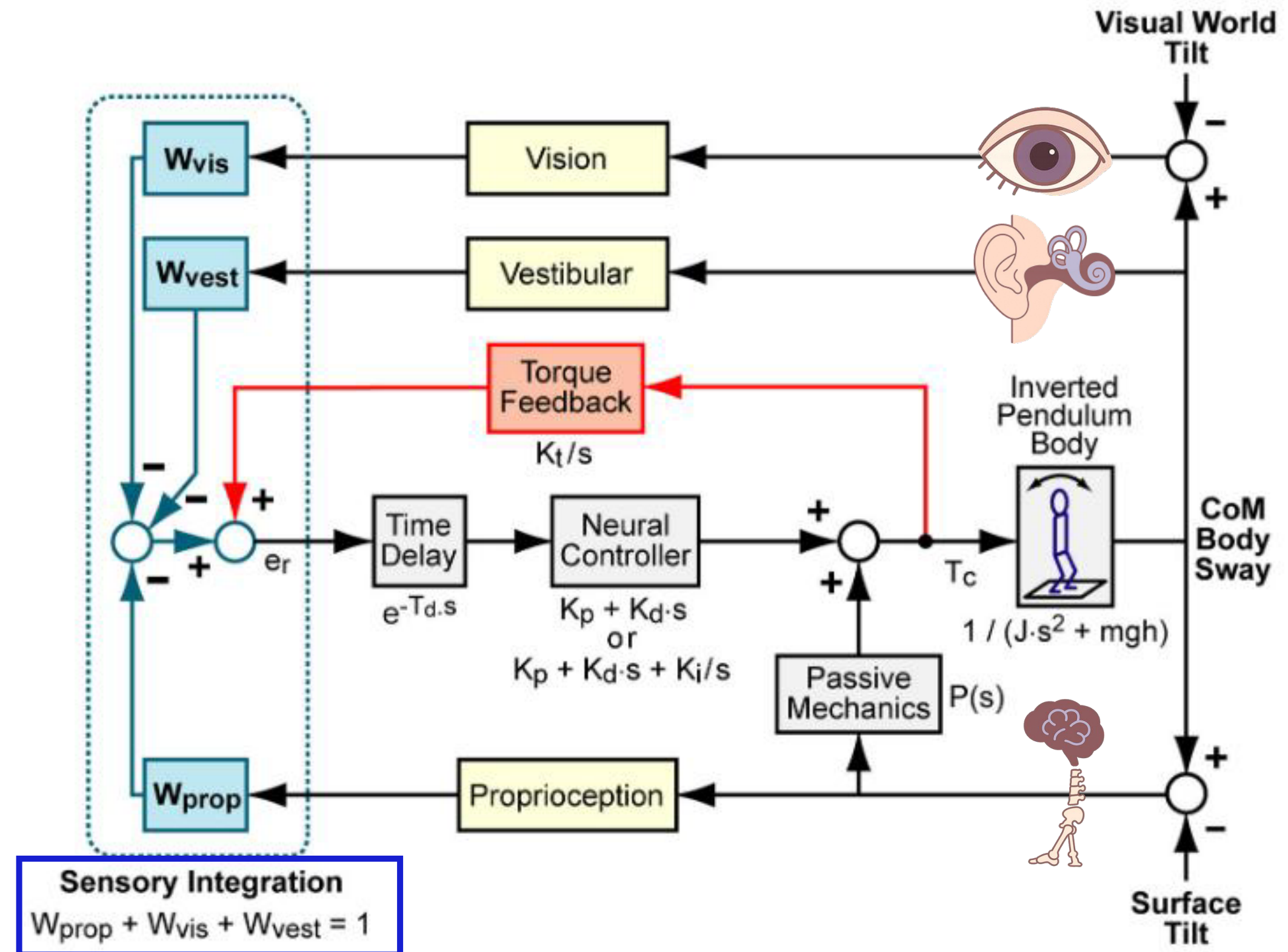
50%



**Système Proprioceptif**



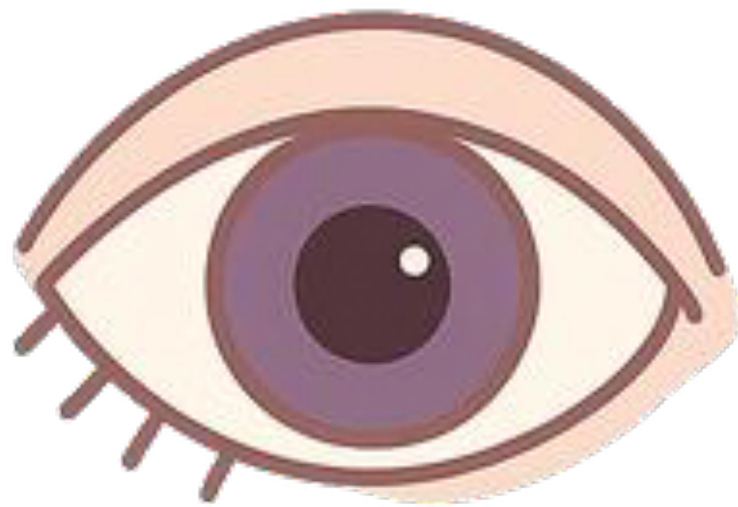
28%

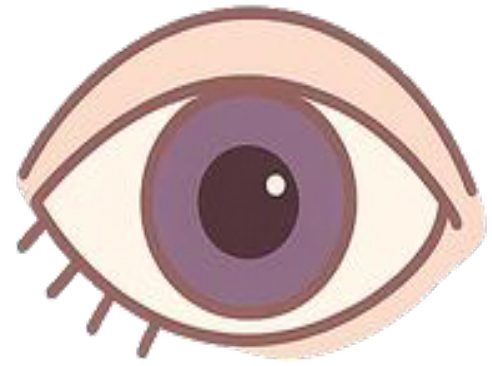


# Objectif général

Evaluer la contribution des systèmes sensoriels dans le contrôle de l'équilibre durant les phases de transitions

## Sous-Objectifs





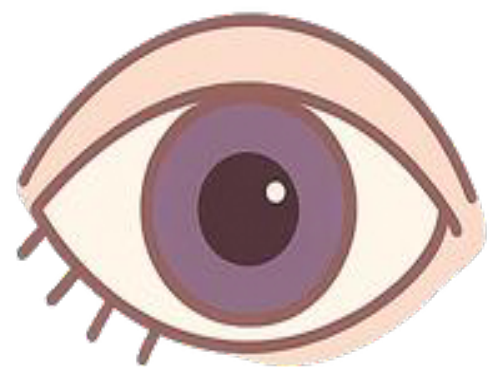
Comment perturber le système visuel  
pour obtenir des réponses posturales ?



**Environnement**

**Type de Stimulus**

**Paramètres du  
Stimulus**



Environnement



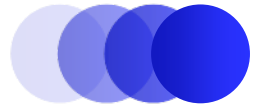
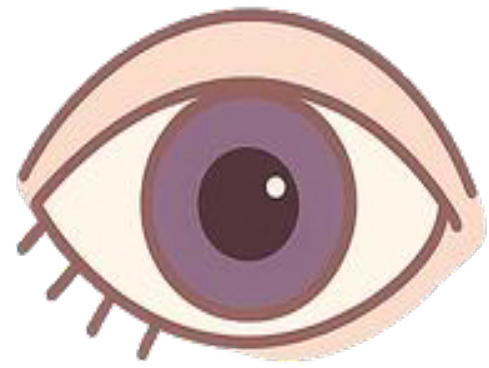
(Lee & Aronson, 1974)



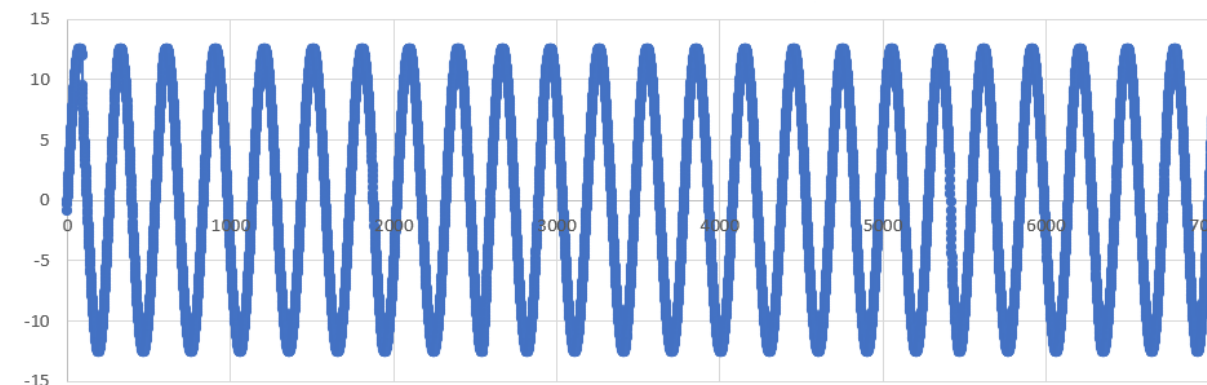
(Delbes, 2022)



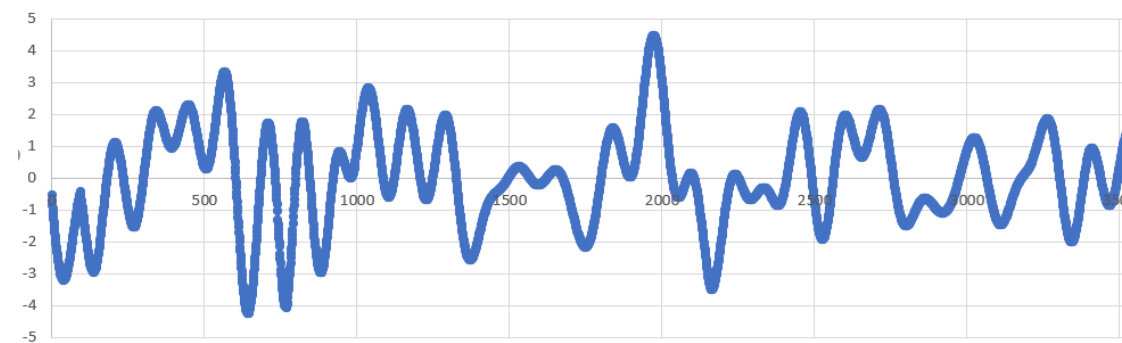
(Peterka, 2002)



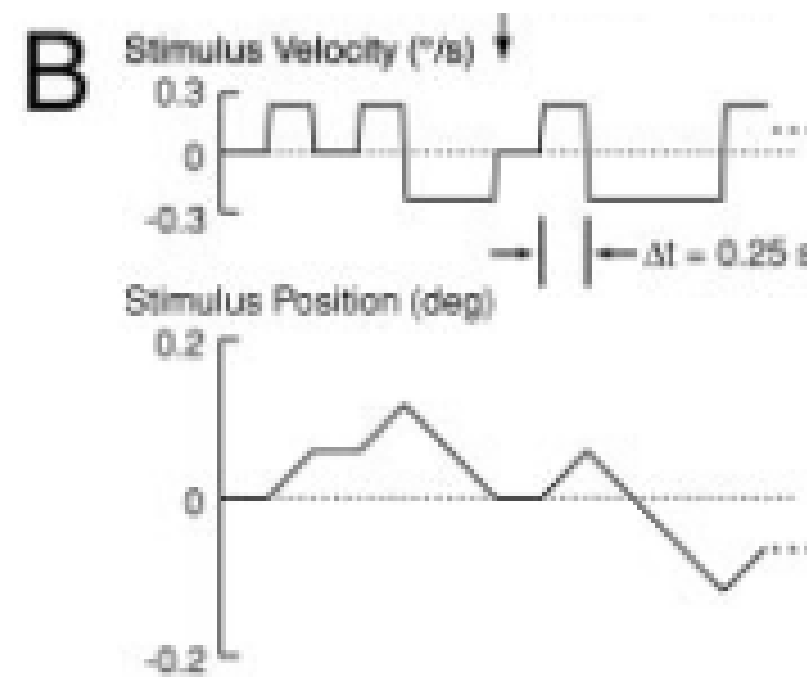
# Type de Stimulus



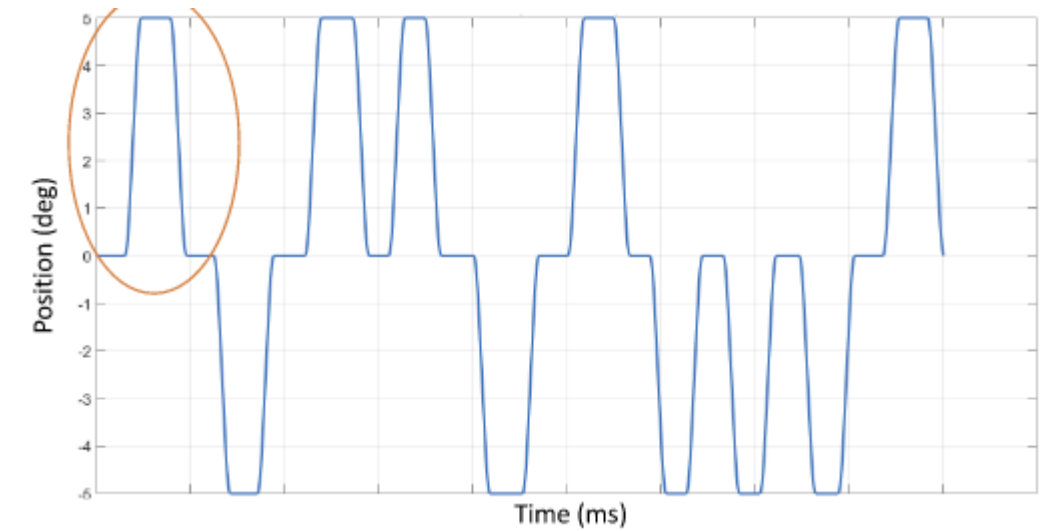
(Van Asten et al., 1988)



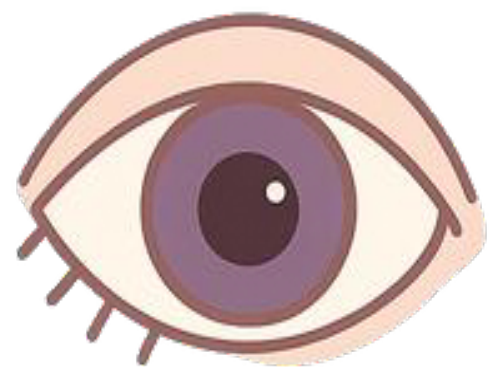
(Martelli et al., 2019)



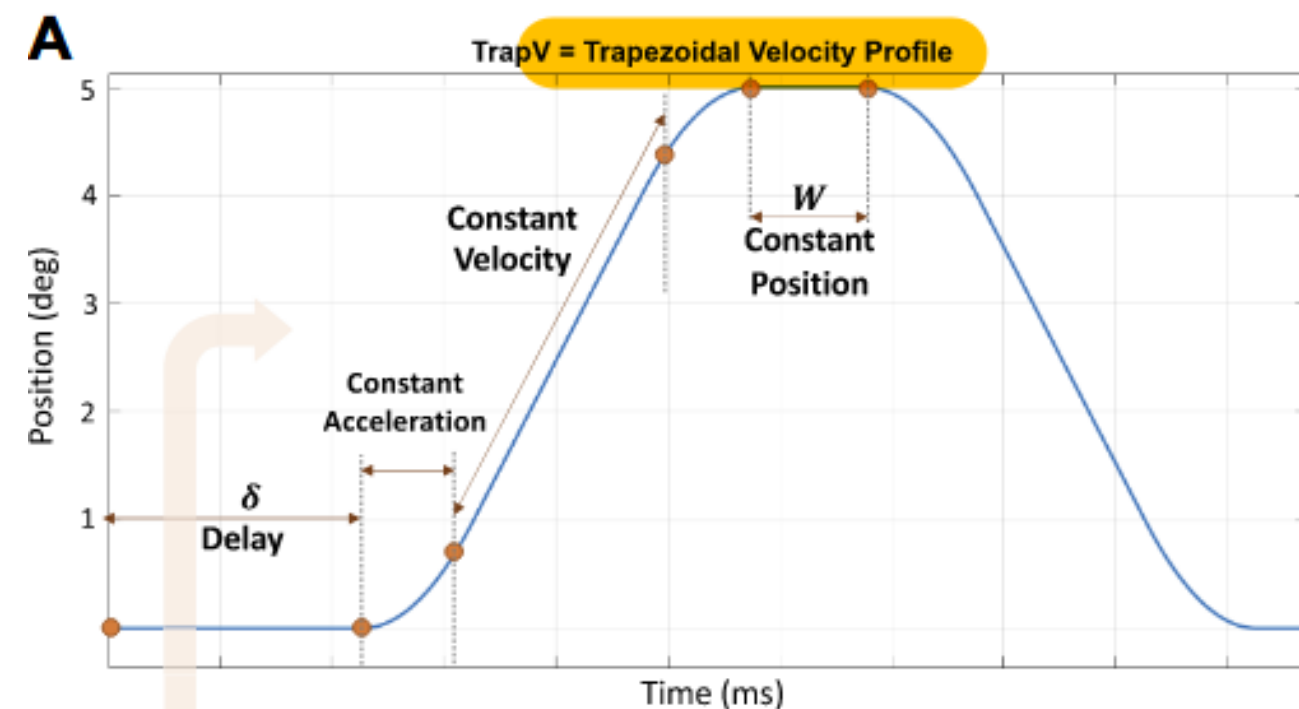
(Peterka, 2002)



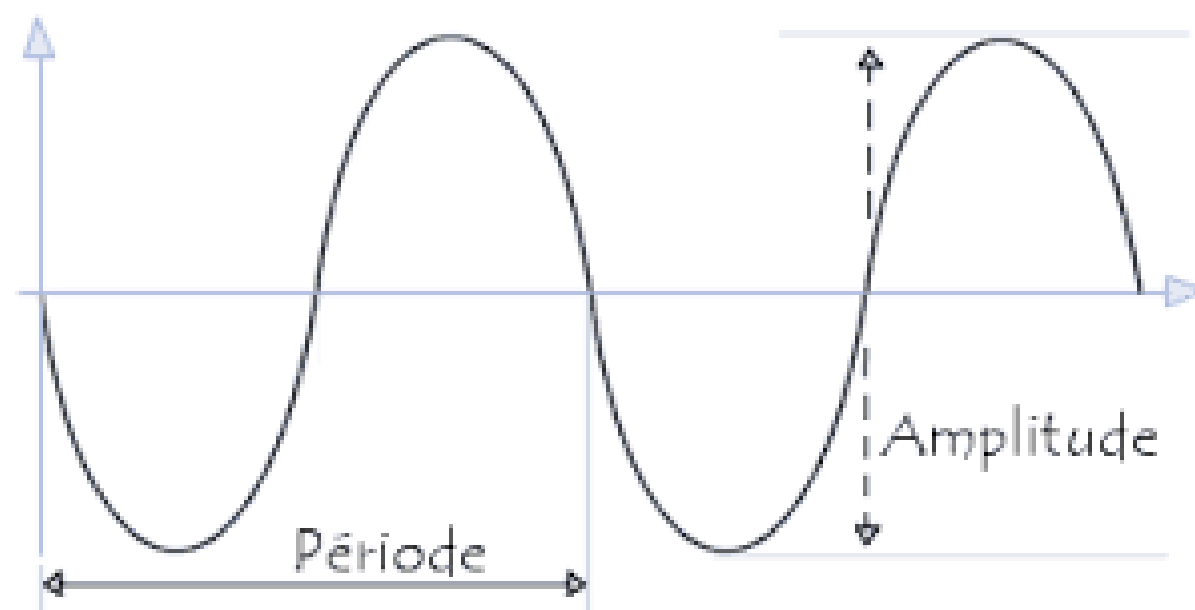
(Mohebbi et al., 2022)



# Paramètres du Stimulus



(Mohebbi et al., 2022)



Rotation



Translation

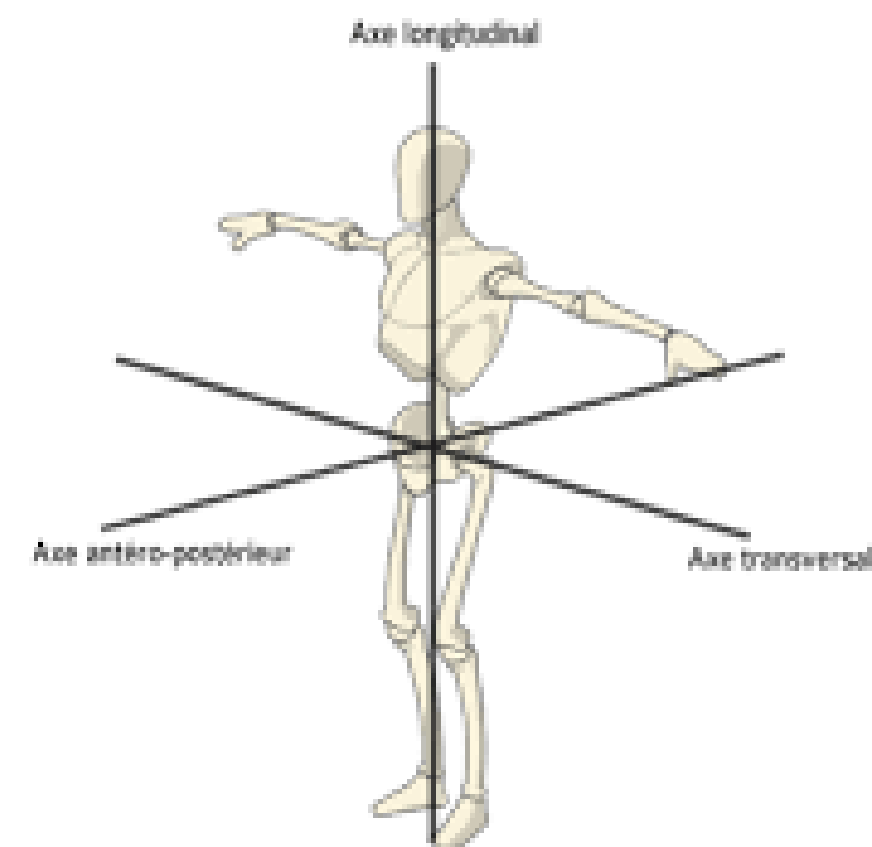
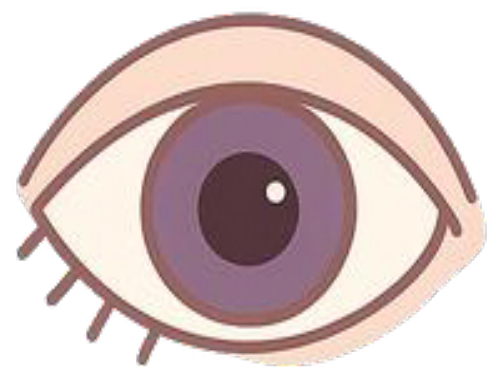


Figure 2 : Axes anatomiques (crédit photo-sci-sport.com)



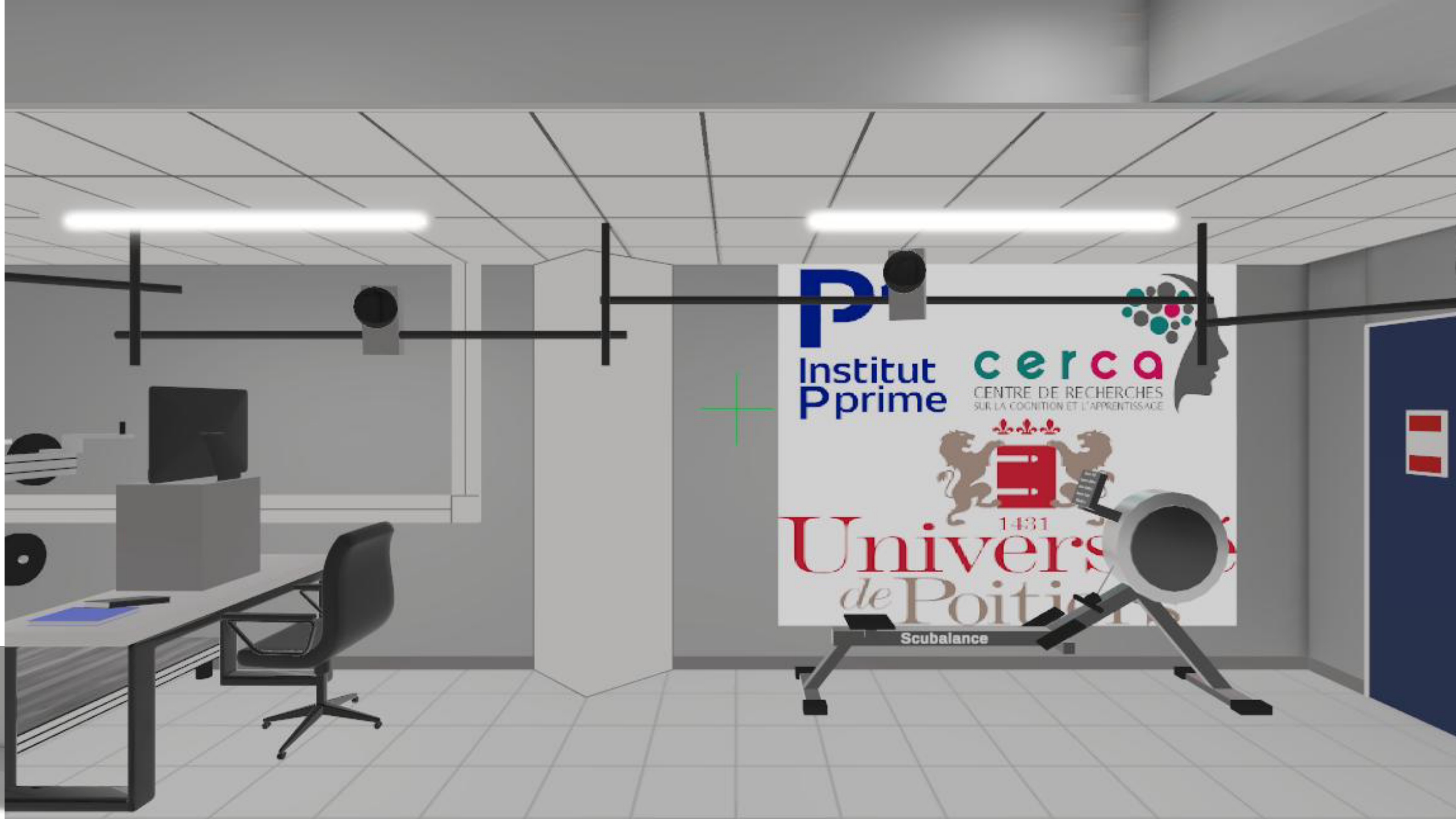
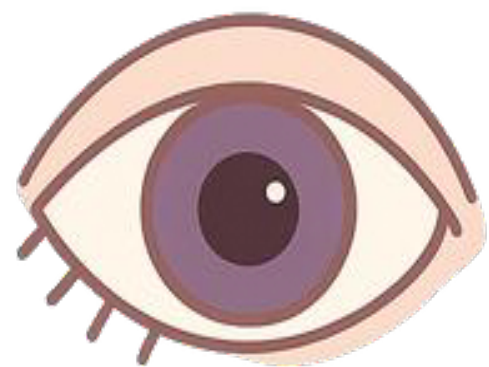
# Concrètement ?

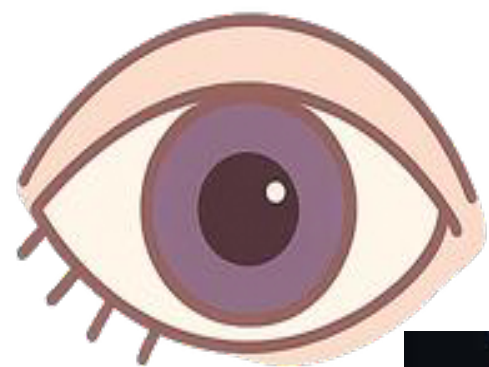


**Environnement**

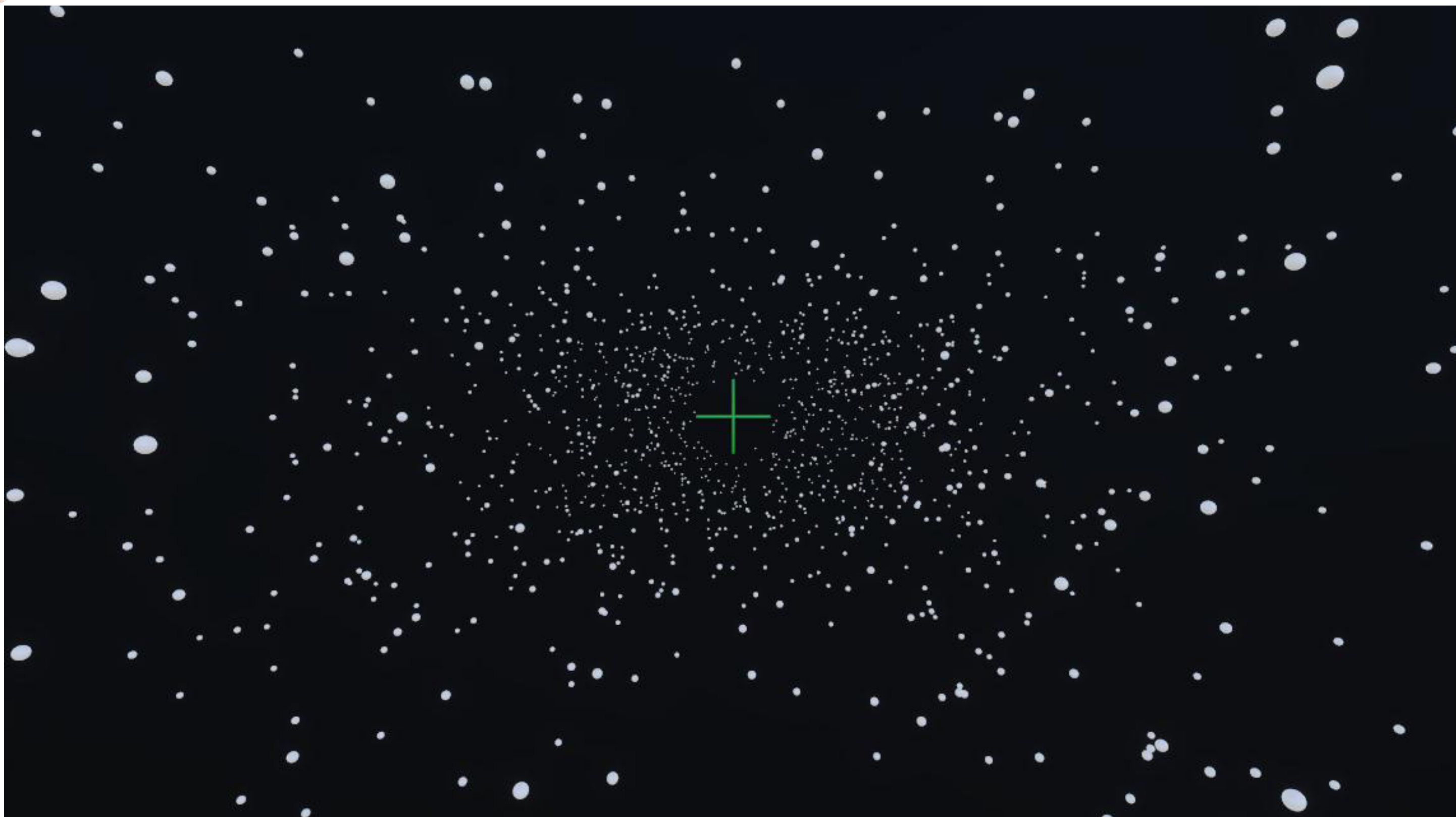
**Stimulus**

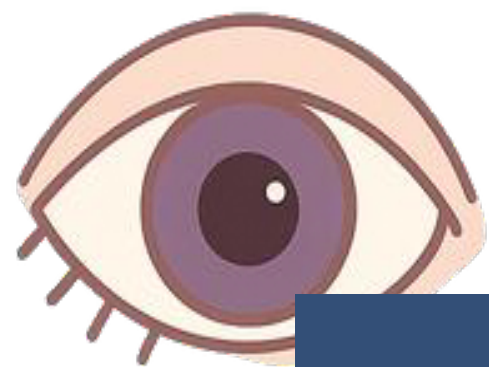
**Traitement et  
Protocole**



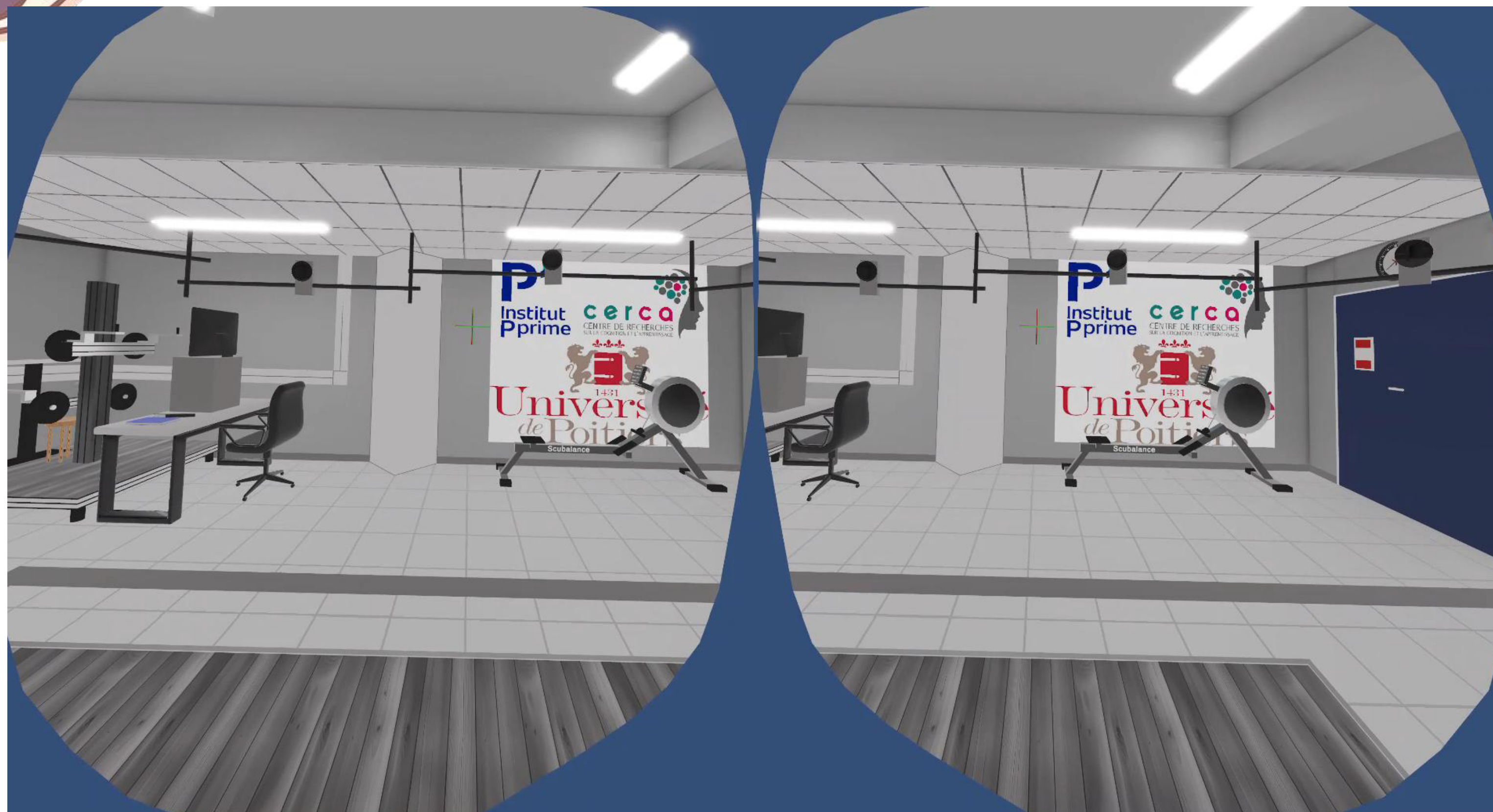


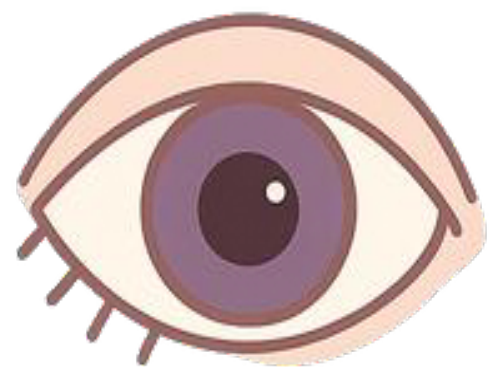
## Création de deux environnements selon la littérature pour comparer leurs effets



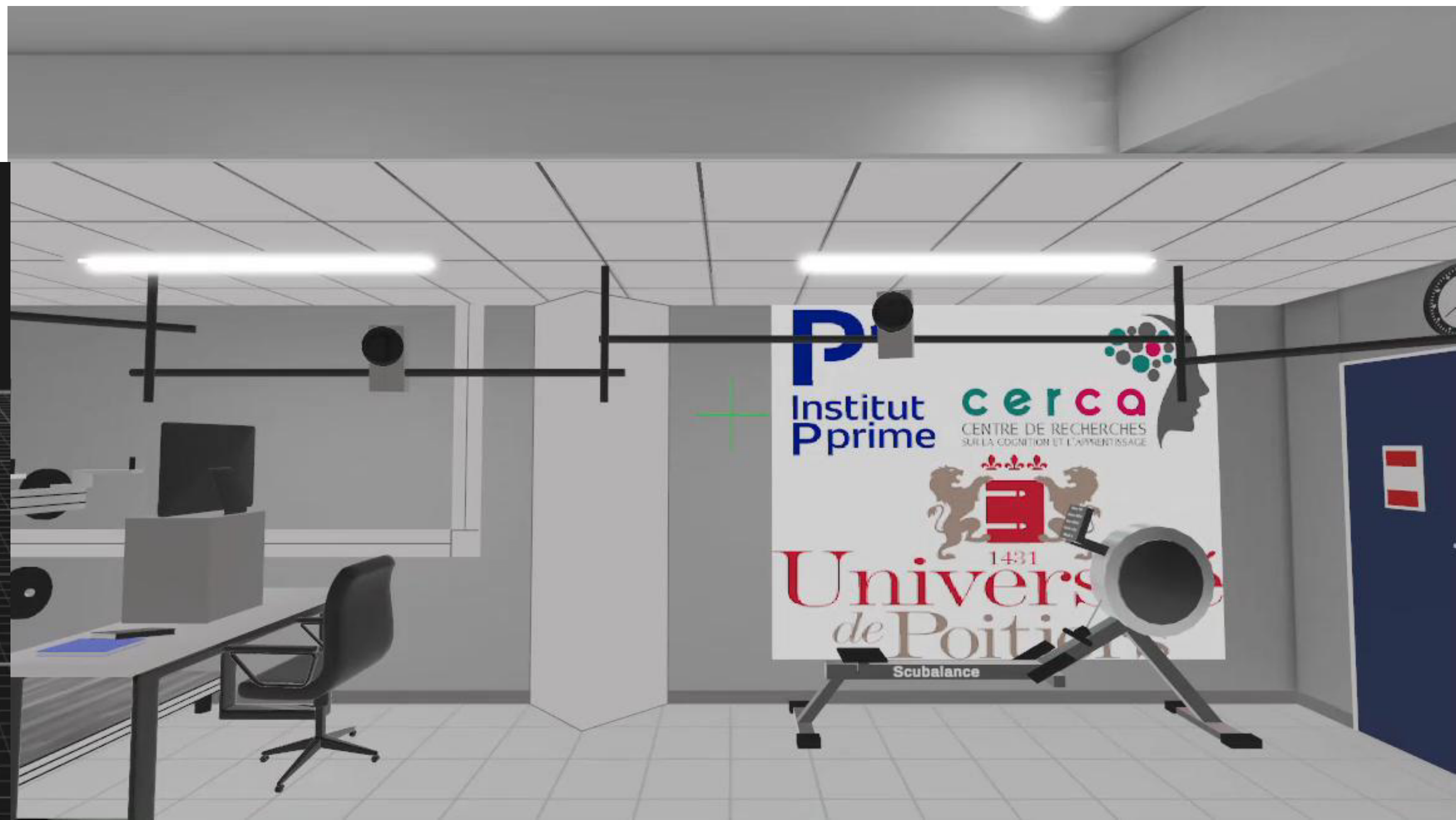
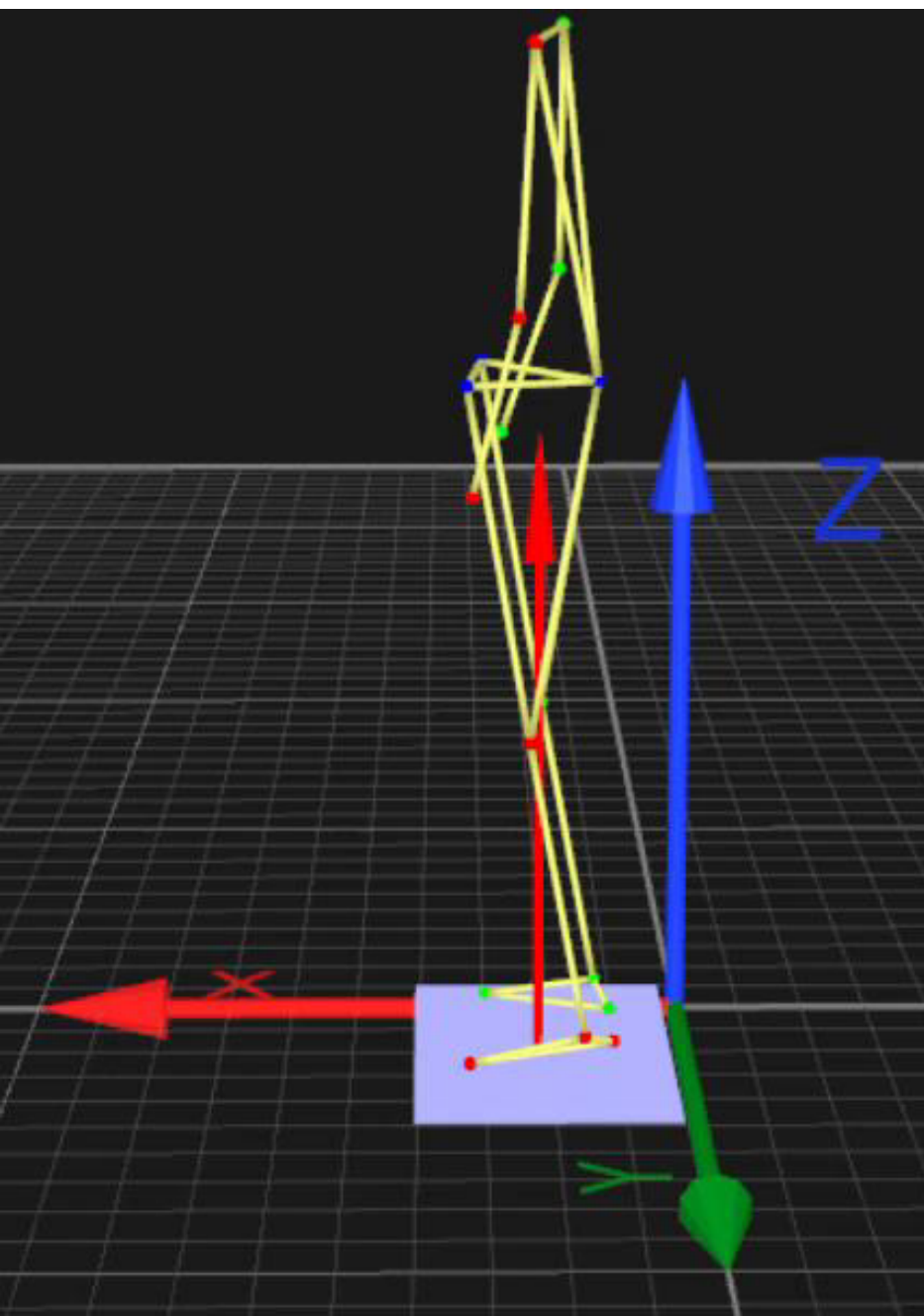


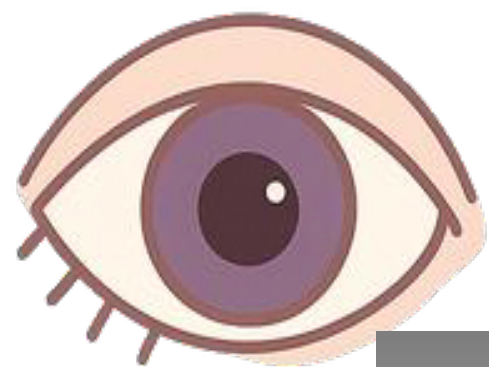
## Création de 4 stimuli par environnement pour comparer leurs effets



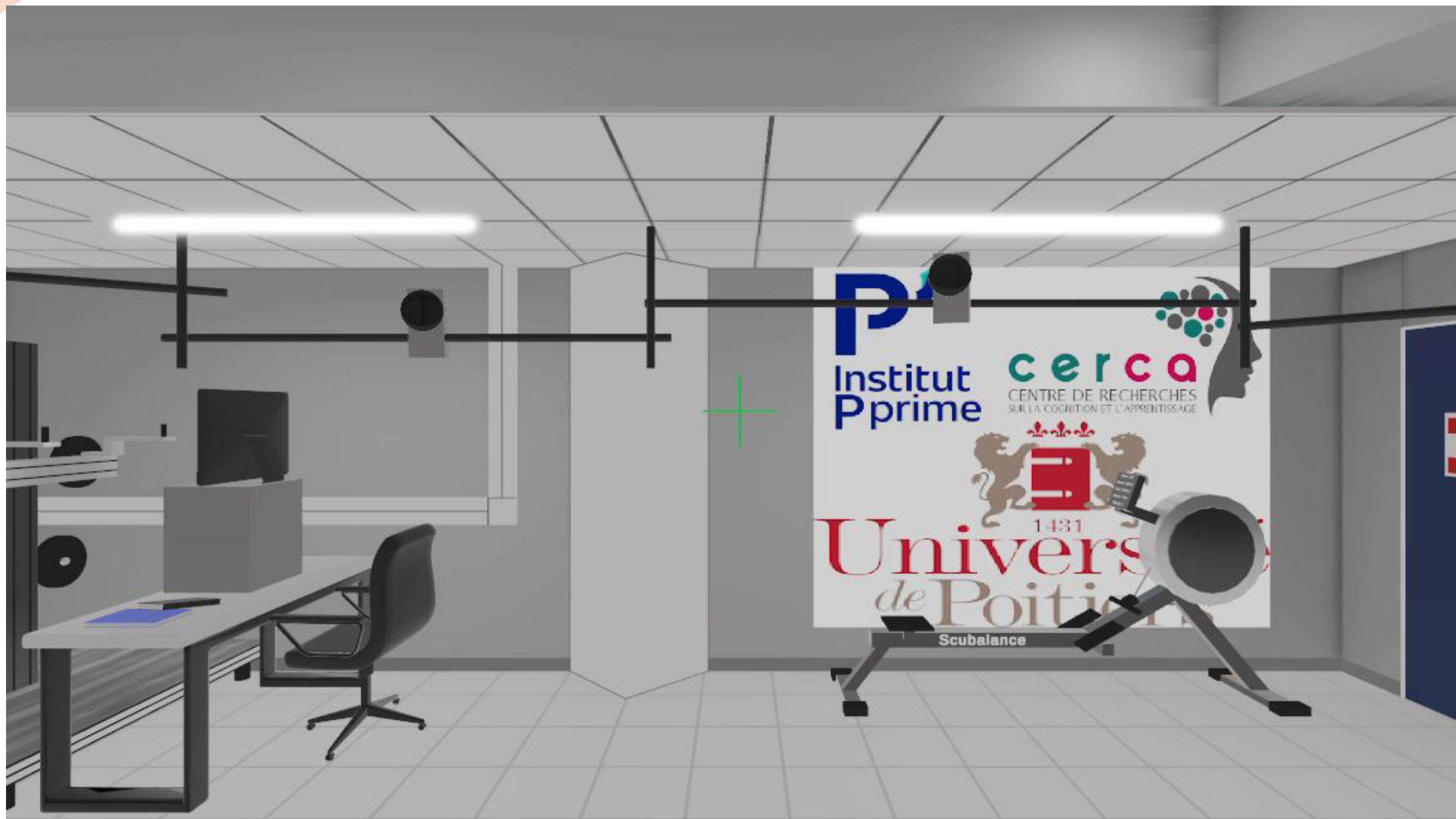


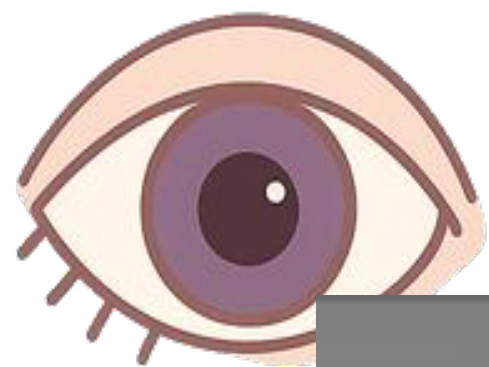
## Création de 4 stimuli par environnement pour comparer leurs effets



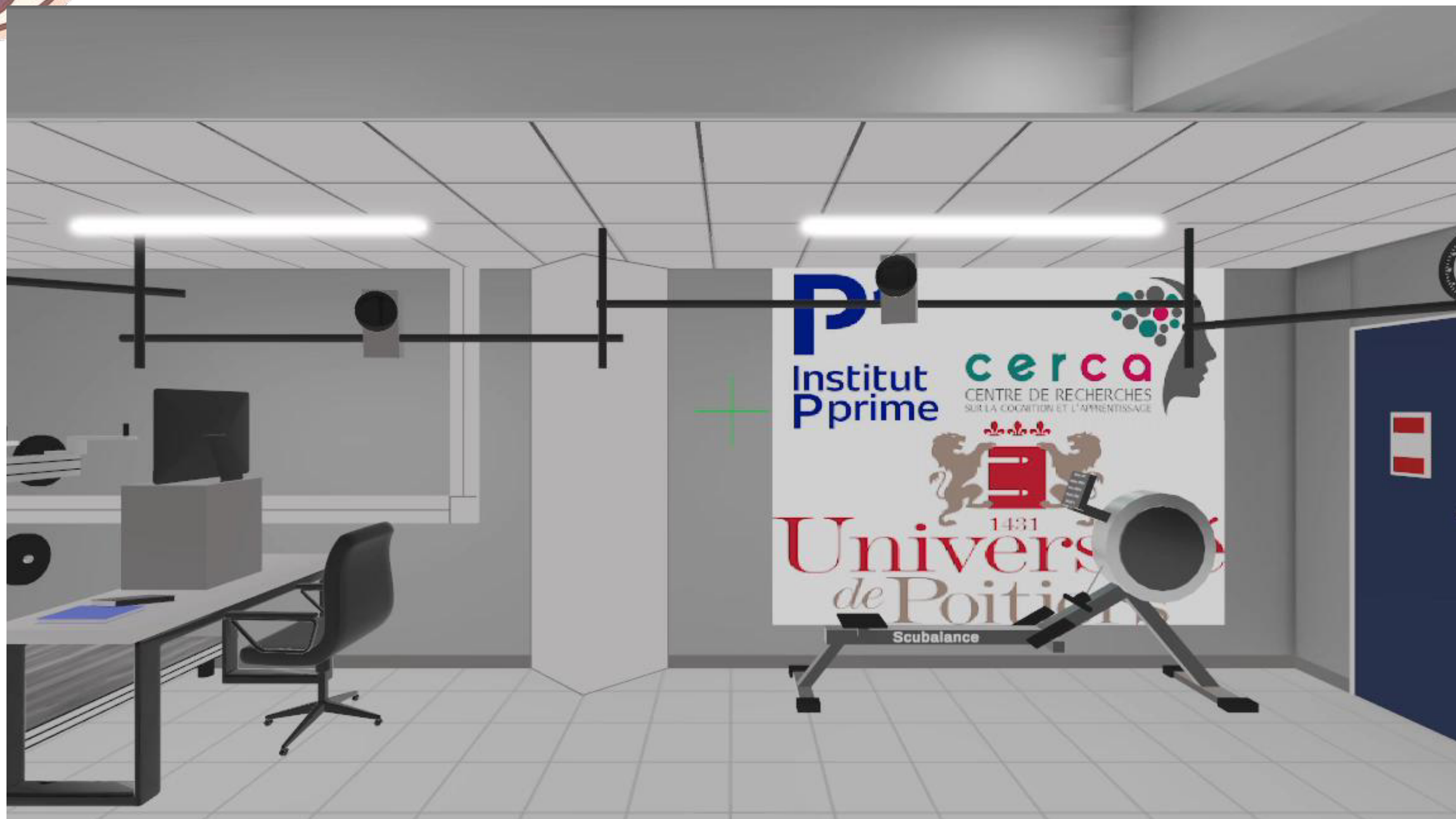


## Création de 4 stimuli par environnement pour comparer leurs effets





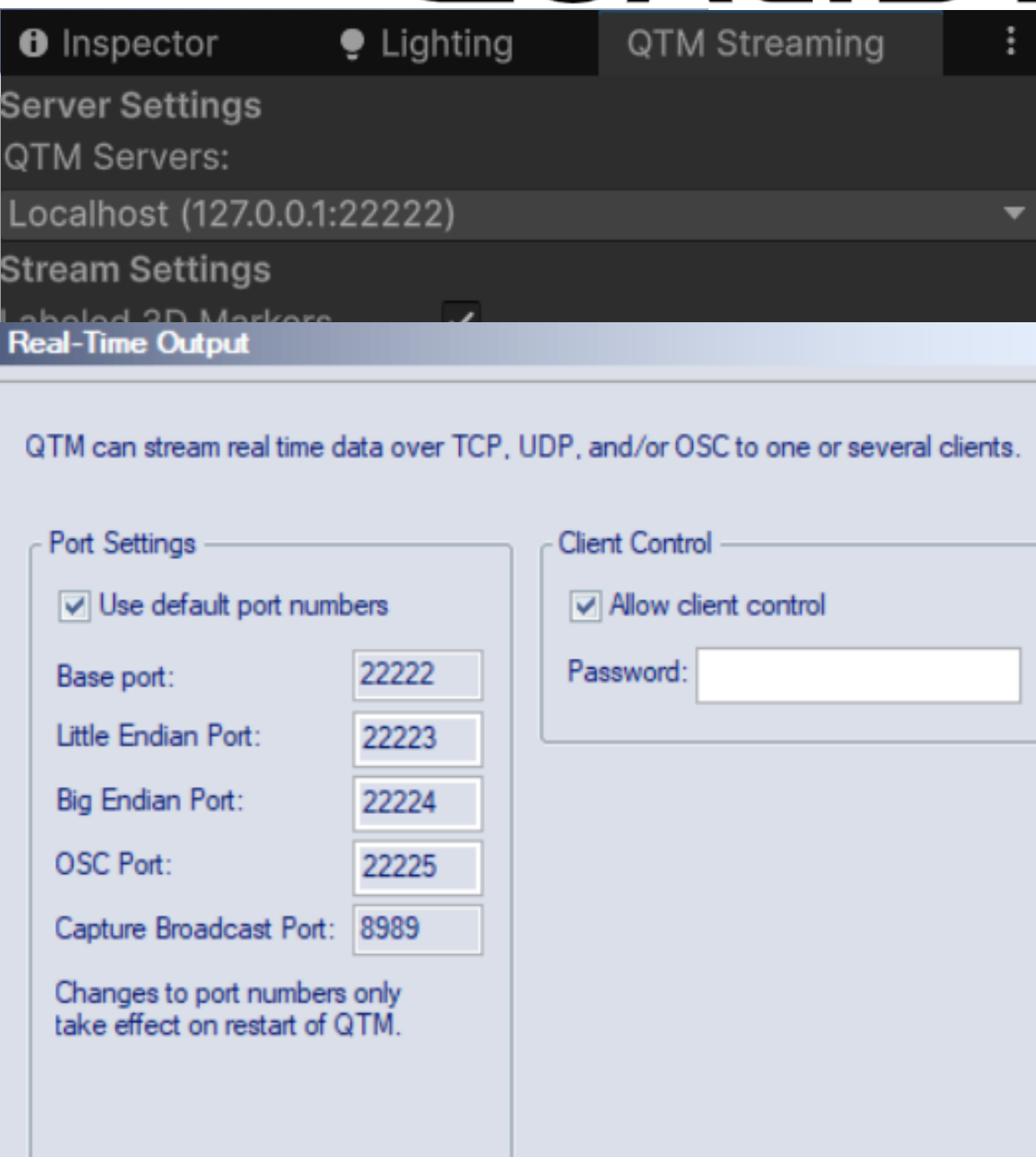
## Création de 4 stimuli par environnement pour comparer leurs effets



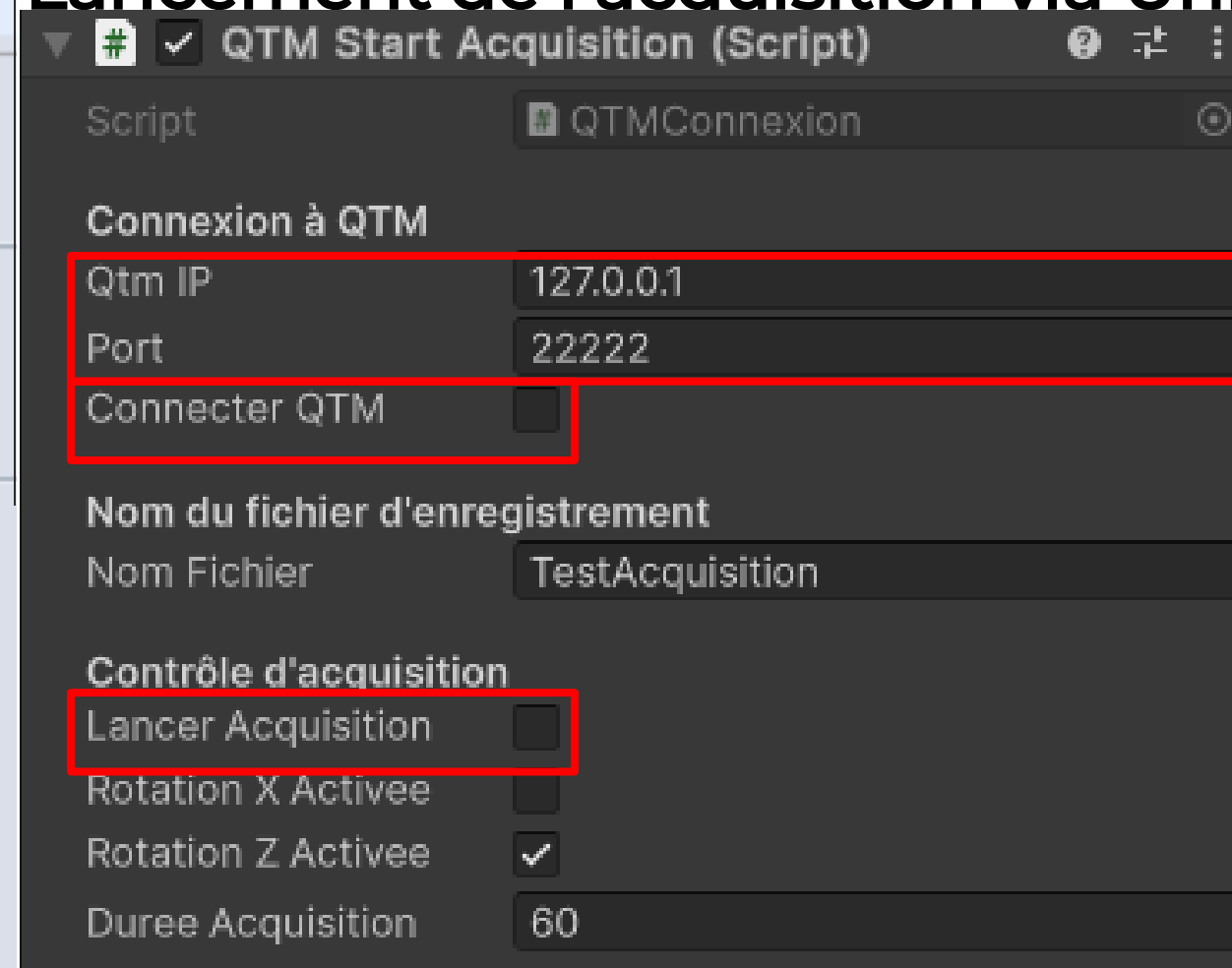
Comment synchroniser les différents systèmes (RV et MOCAP) pour analyser les données obtenues ?

QUALISYS

Qualisys Unity SDK



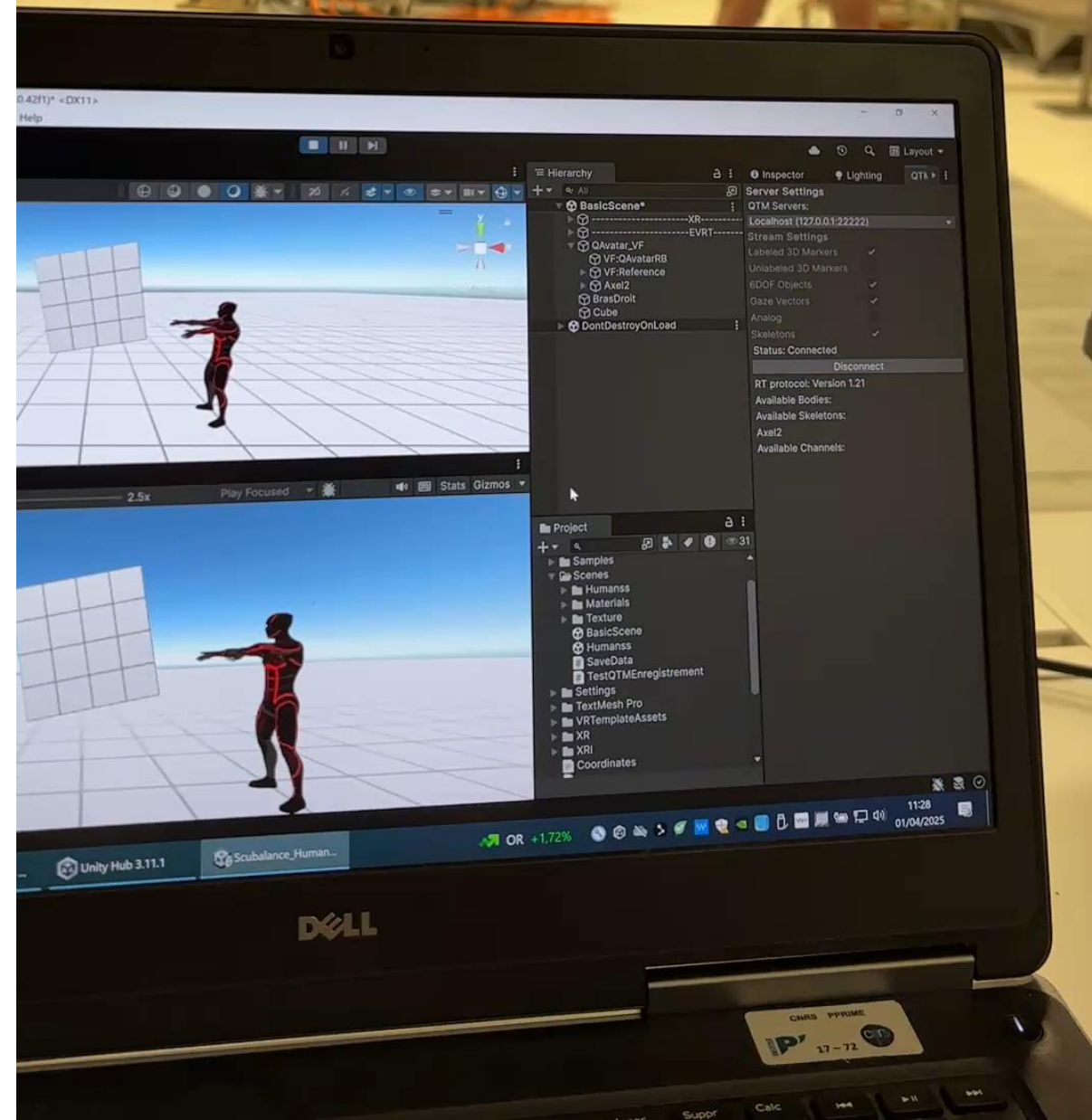
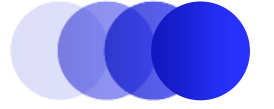
Lancement de l'acquisition via Unity

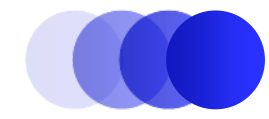


C  
sys



ts  
ser

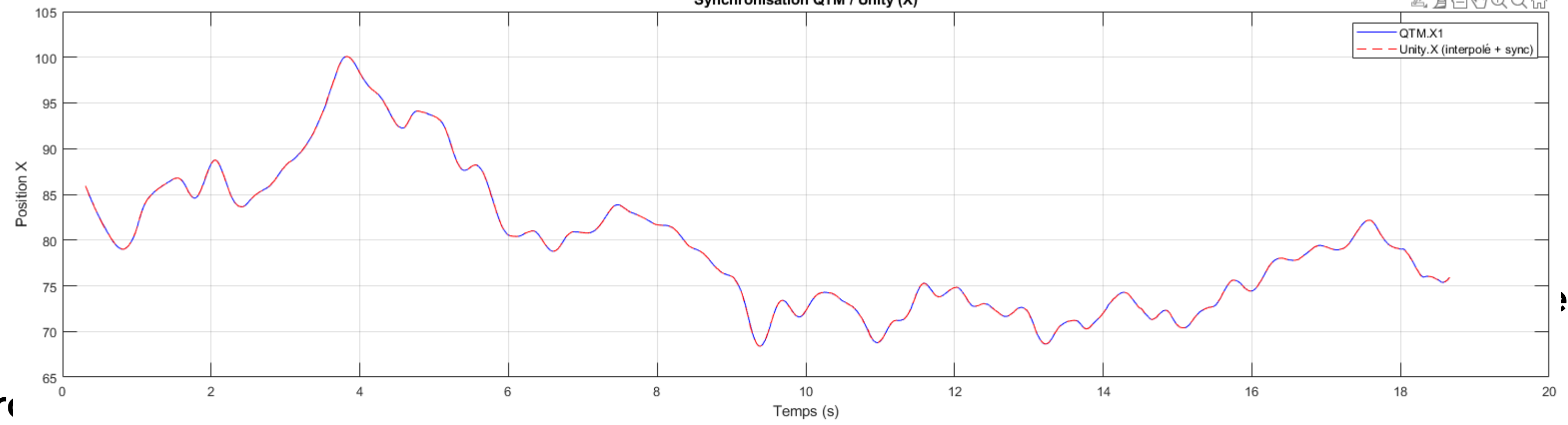




Export OTM

Export Unity

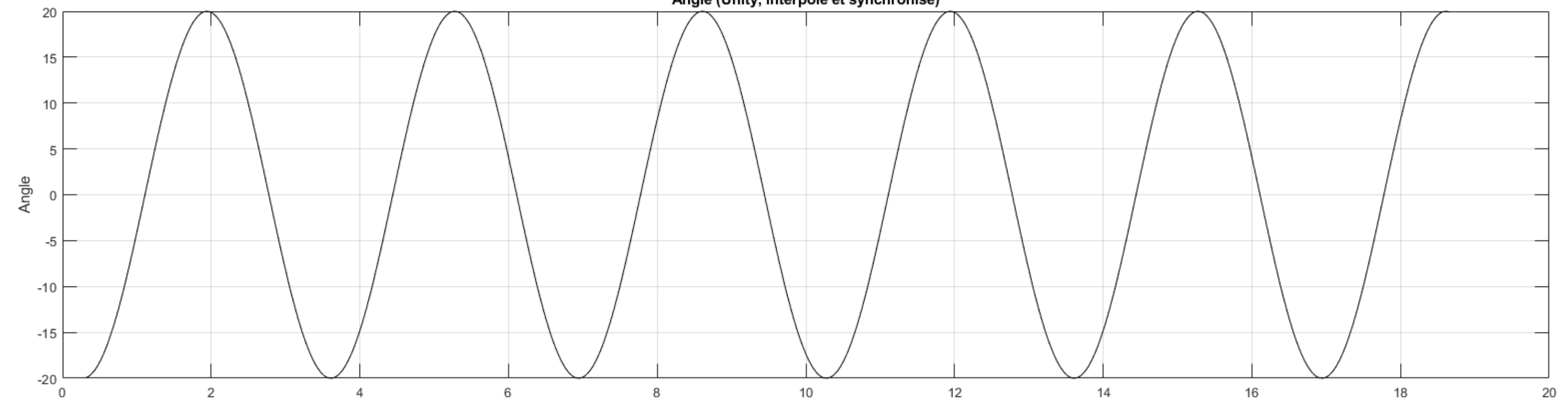
Synchronisation QTM / Unity (X)



For

QTM : 100.00 Hz | Unity : 62.53 Hz  
Décalage estimé : -31 échantillons (-0.310 s)  
Différence moyenne absolue : 0.02 mm | Ecart-type de la différence : 0.03 mm

Angle (Unity, interpolé et synchronisé)



QTM

Static

Tag 

Untagged

 Layer 

Default

Transform

Position

X 0 Y 0 Z 0

Rotation

X 0 Y 0 Z 0

Scale

X 1 Y 1 Z 1

QTM Start Acquisition (Script)

Script 

QTMConnexion

Connexion à QTM

Qtm IP

127.0.0.1

Port

22222

Connecter QTM

Nom du fichier d'enregistrement

Nom Fichier

TestAcquisition

Contrôle d'acquisition

Lancer Acquisition

Rotation X Activee

Rotation Z Activee

Duree Acquisition

60

Rotation Control During Acquisition (S)

Rotation pendant acquisition

Acquisition Script

QTM (QTM Start Acquisition)

Objet A Rotater

-----EVRT-----

Marker

Marker

Mode

Sinusoidal

Paramètres généraux

Amplitude

10

Frequence

0.2

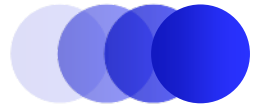
Vitesse max : 12,6°/s

Vitesse moyenne : 8,0°/s

Rotation simulée (angle en degrés)

Add Component

# Interface dans Unity facilement utilisable pour paramétrer les stimuli



Rotation Control During Acquisition

Rotation pendant acquisition

Acquisition Script

QTM (QTM Start Acquisition)

Objet A Rotater

-----EVRT-----

Marker

Marker

Mode

Stochastique

Paramètres généraux

Amplitude

10

Paramètres stochastiques

Sinusoids

4

Element 0

Amplitude 1

Frequence 0.16

Phase Degres 0

Element 1

Amplitude 0.8

Frequence 0.21

Phase Degres 0

Element 2

Amplitude 1.4

Frequence 0.24

Phase Degres 0

Element 3

Amplitude 0.5

Frequence 0.49

Phase Degres 0

Vitesse max estimée : 31,4°/s

Vitesse moyenne estimée : 20,0°/s

Rotation simulée (angle en degrés)

QTM Translation (Script)

Translation pendant acquisition

T\_acquisition Script

QTM (QTM Start Acquisition)

T\_objet A Translater

Translation

T\_marker

Marker

T\_mode

Trap V

Paramètres TrapV

Trap Amplitude

5

Trap Vitesse

5

Trap Duree Plateau B

2.5

Inverser Aleatoiremei

Générer les inversions aléatoires

Translation simulée (m) & Vitesse (m/s)

Déplacement

Vitesse

QTM Start Acquisition (Script)

Script 

QTMConnexion

Connexion à QTM

Qtm IP

127.0.0.1

Port

22222

Connecter QTM

Nom du fichier d'enregistrement

Nom Fichier

TutoUnity

Contrôle d'acquisition

Lancer Acquisition

Rotation X Activee

Rotation Z Activee

Duree Acquisition

15

Rotation Control During Acquisitic

Rotation pendant acquisition

Acquisition Script

QTM (QTM Start Acquisition)

Objet A Rotater

-----EVRT-----

Marker

Marker

Mode

Sinusoidal

Paramètres généraux

Amplitude

15

Frequence

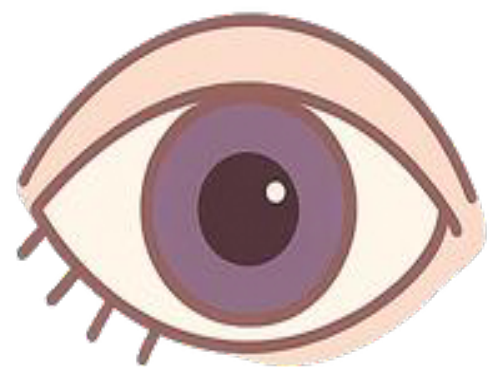
0.3

Vitesse max : 28,3°/s

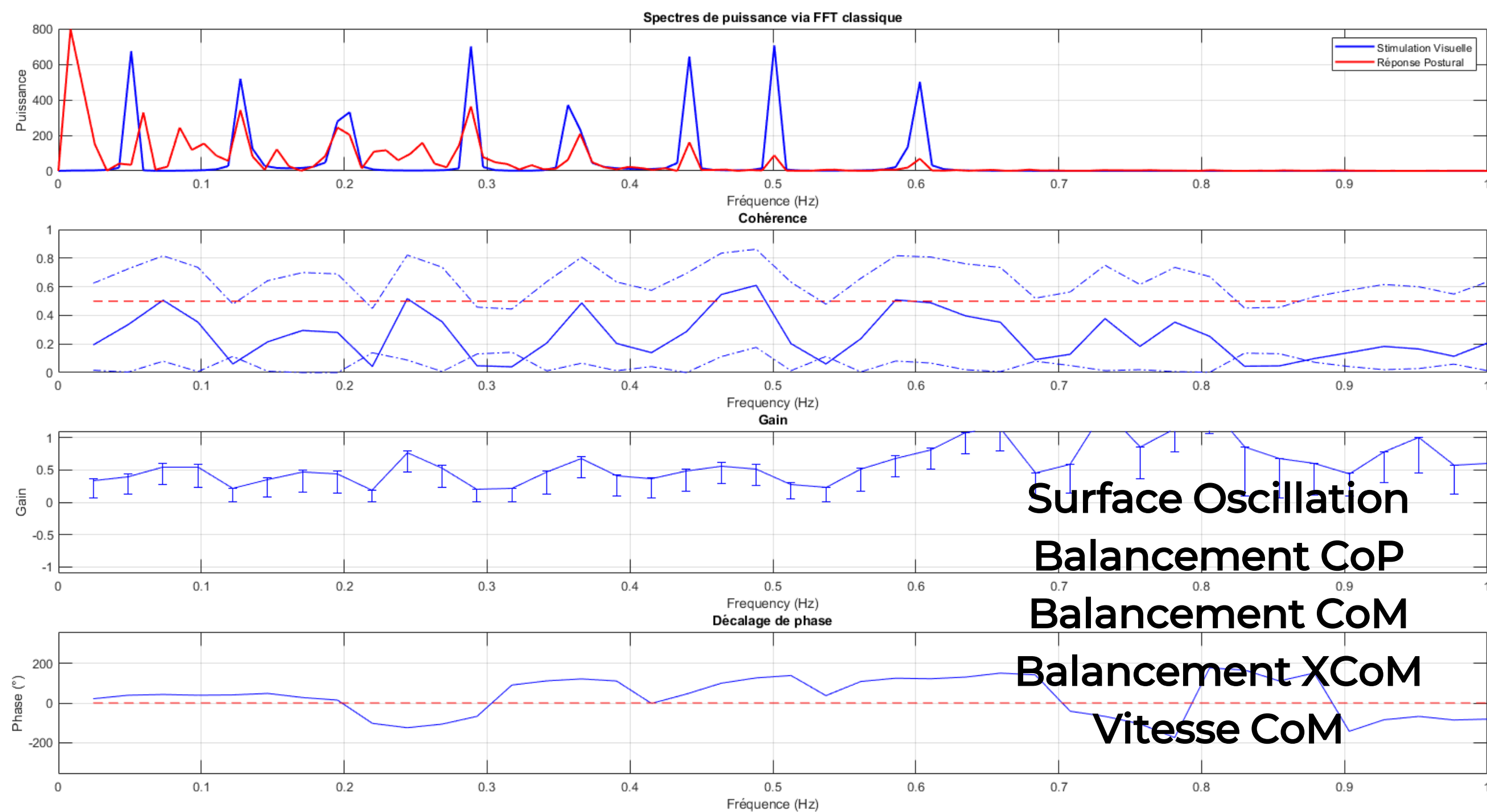
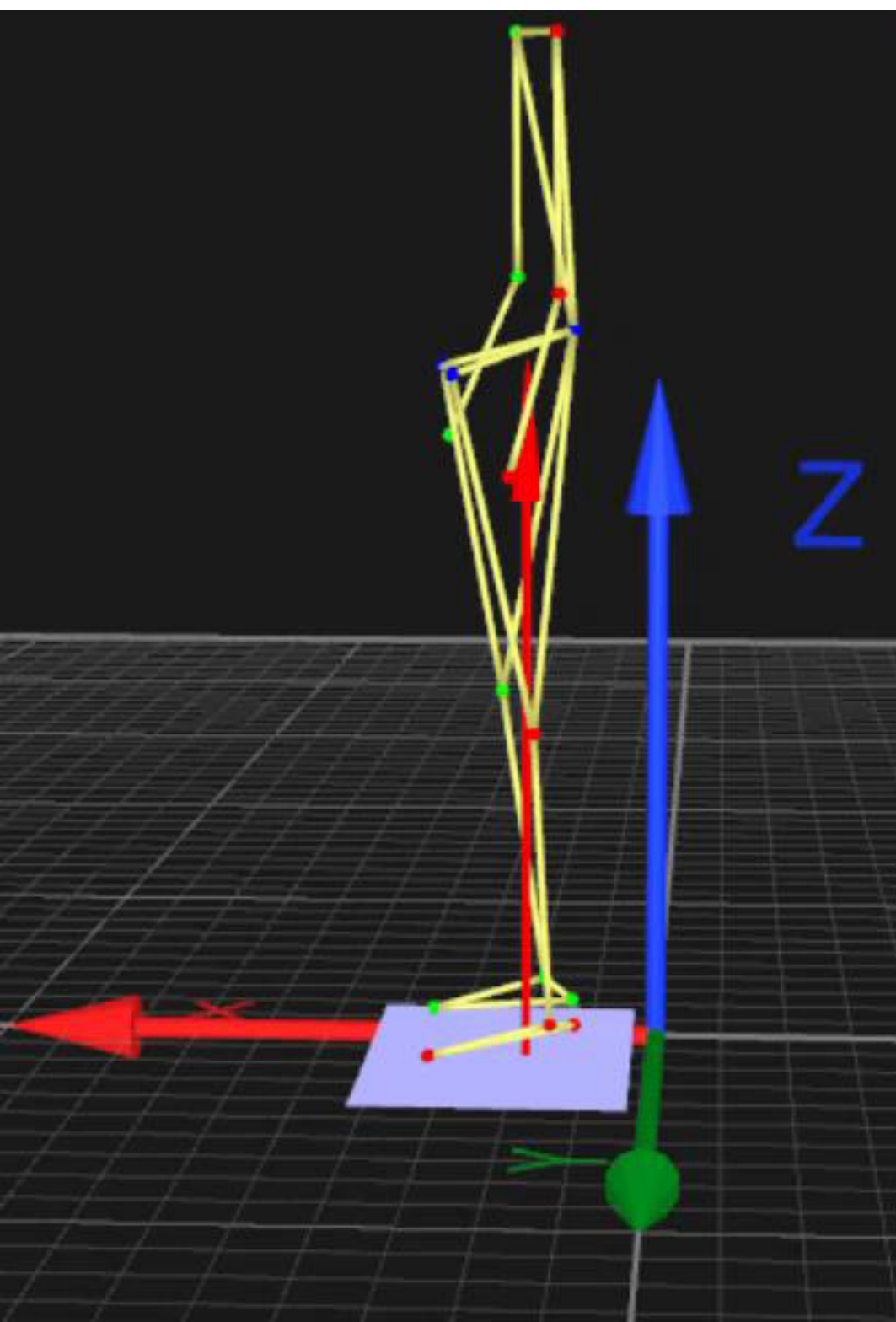
Vitesse moyenne : 18,0°/s

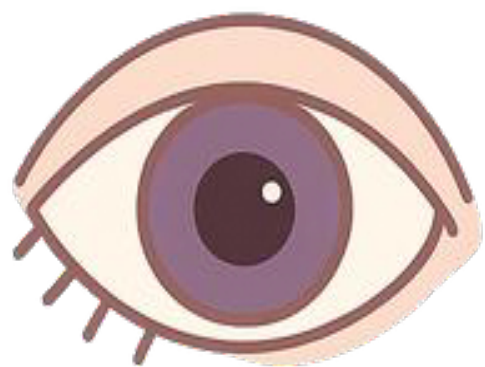
Rotation simulée (angle en degrés)

Asset Labels

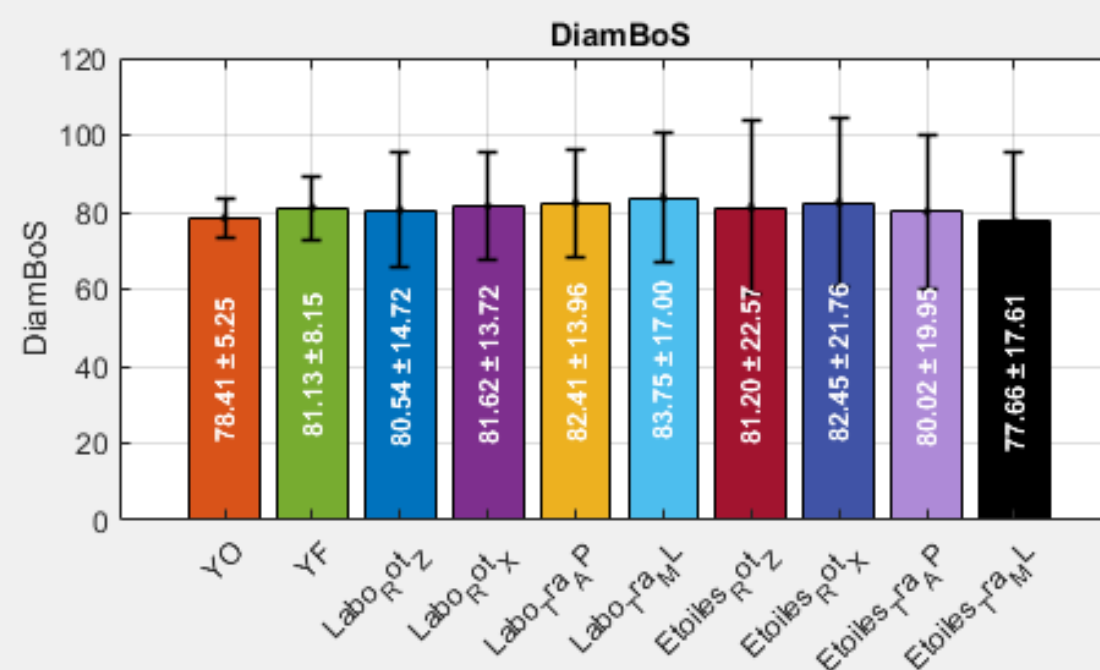
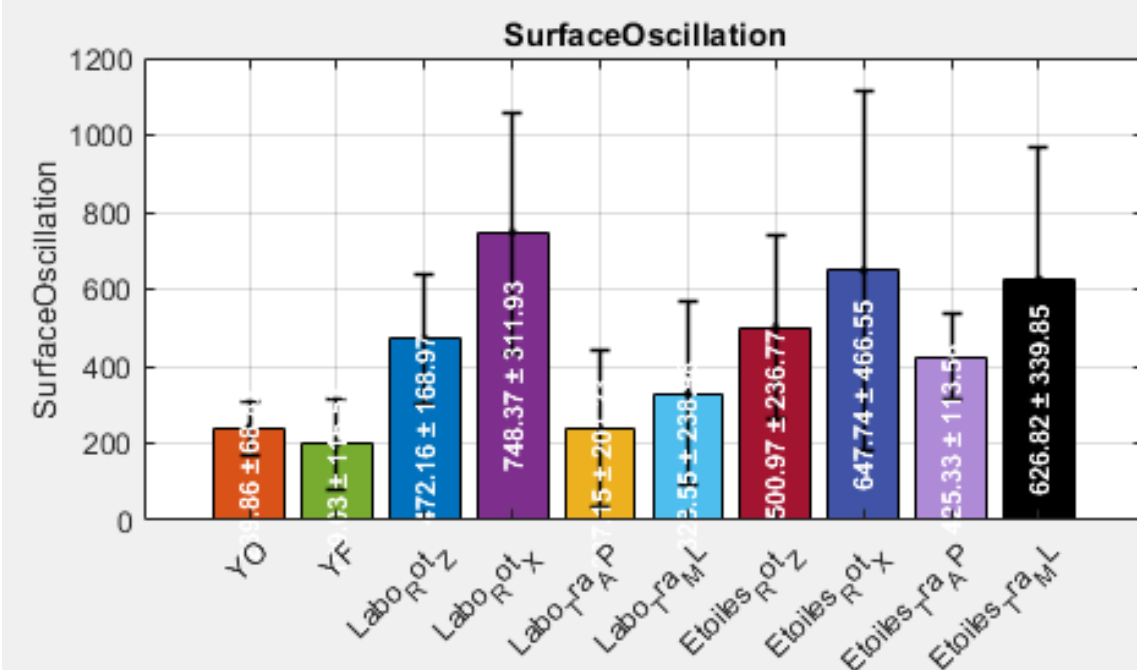
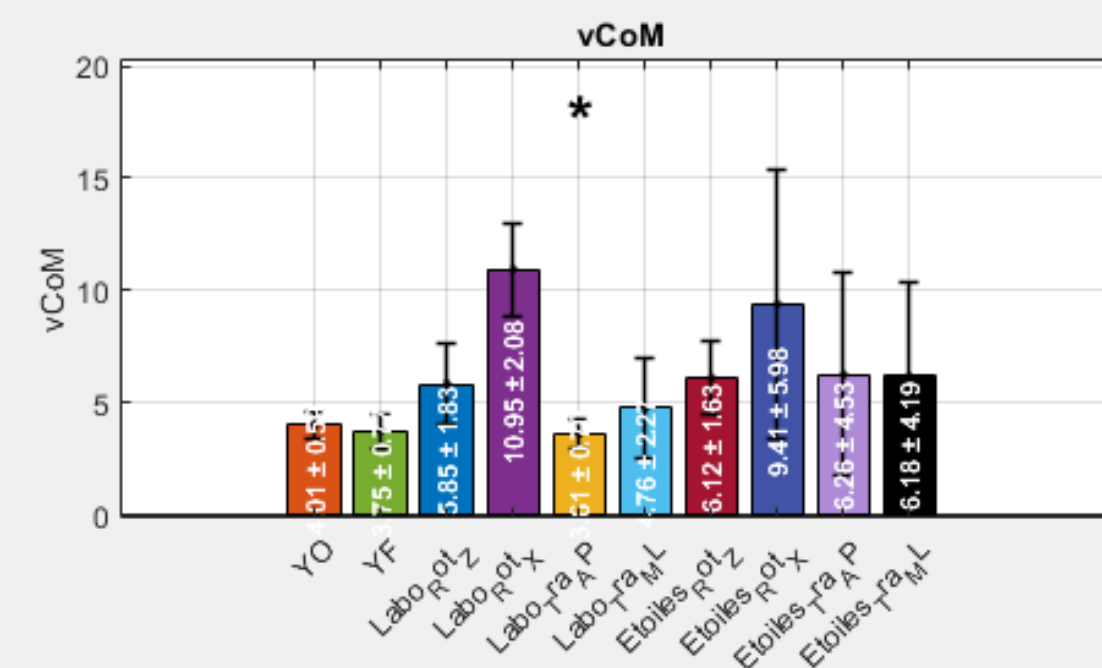
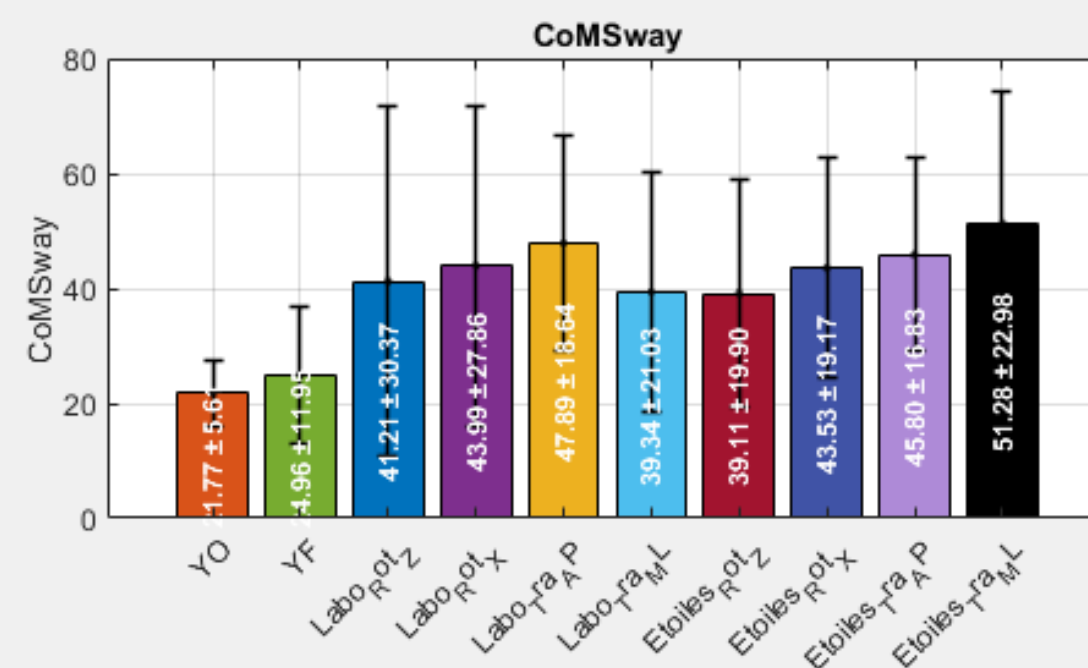
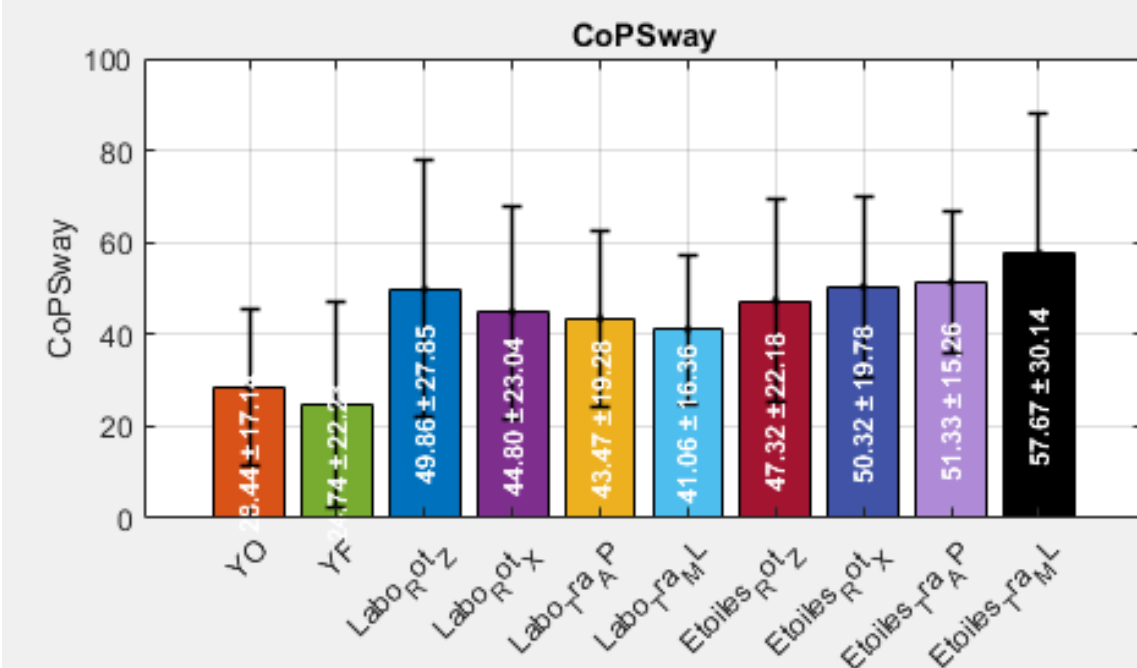


# Routine de traitement pour exploiter les données reliant stimulus visuel et réponses posturales





# Routine de traitement pour exploiter les données reliant stimulus visuel et réponses posturales





# SCUBALANCE

**Optimisation de stimuli visuels induisant  
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**05/06/25**