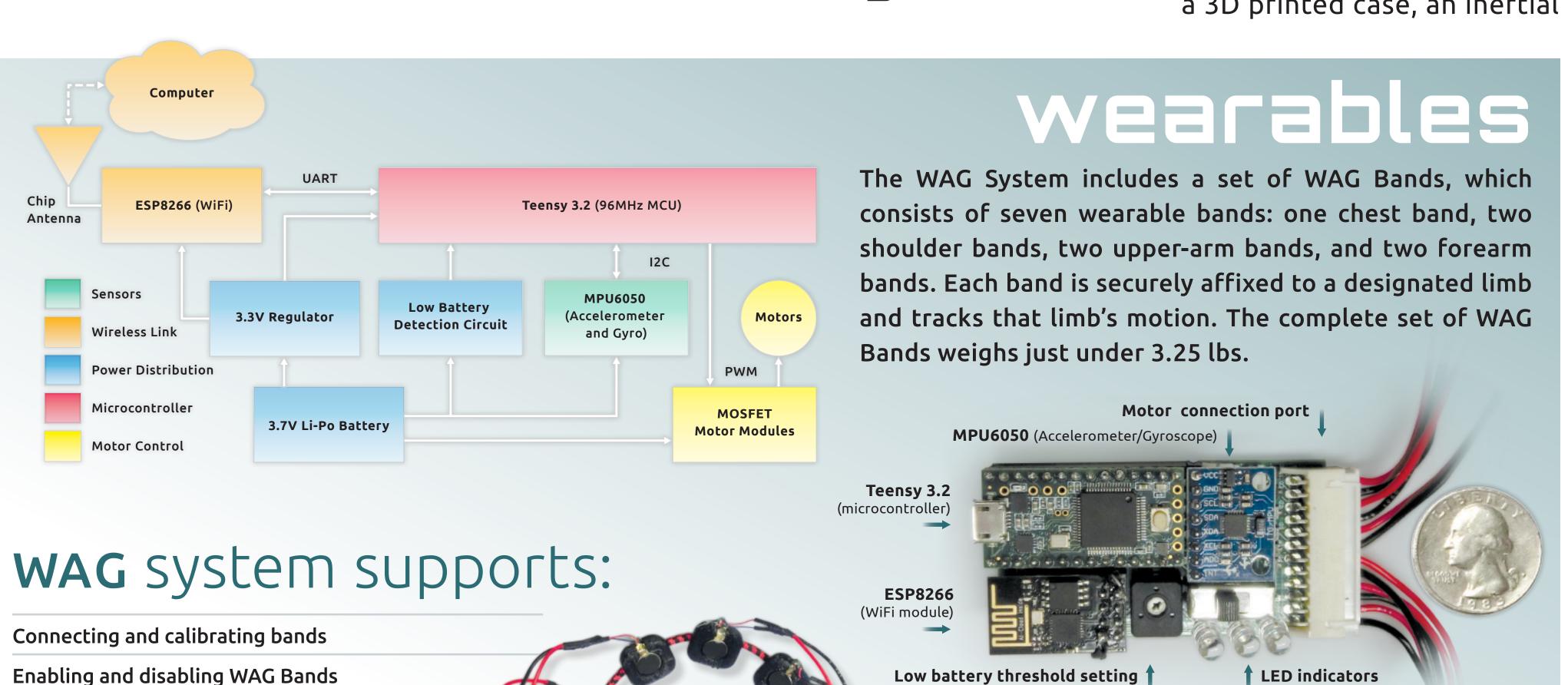


Wearable Action Guidance System

abstract the wearable action guidance (wag) system

is a training tool designed to improve the efficiency and convenience of teaching and learning new physical skills, while matching or exceeding the quality of feedback received from an in-person trainer. The system consists of a computer application and a set of wearable bands; each band comprises a 3D printed case, an inertial measurement unit, a battery, a ring of vibration motors, and a secure strap. Trainers can use the WAG System to record and save motions for distribution to trainees, while trainees can use the system to play back those motions with directed vibratory feedback. Initial prototypes have attracted potential partners interested in introducing the technology to various markets including athletic training and physical rehabilitation.



Playing: Second motion ▶ 00:00.00

To calibrate the WAG System, a user matches the full-body pose shown by the software application. This establishes a position reference for all of the WAG Bands in space.

User Interface Input File System/Library **Visualization** Positional Error Single Band Position **Voice Commands** Stop Recording **Hardware Bands**

The WAG System also includes a software application with a graphical user

interface, written in C++, which runs on the user's computer. The application

is responsible for collecting and manipulating each band's orientation data

and is the primary interface between the user and the WAG Bands.

software

Enabling and disabling WAG Bands Displaying band disconnect notifications Monitoring band battery status Managing WiFi communications

Saving 10 minutes of continuous movement in one motion file

Cropping recorded motions

Loading motion files for playback

Maintaining and accessing a motion library

Playing back motions in continuous or step-through modes

Specifying motion playback speeds

Visualizing user motion

Indicating error via haptic feedback with under 0.1 seconds of latency

Measuring 9 degrees of freedom per arm

Playing back motion for up to 2 hours on battery power

Recording motion for up to 6 hours on battery power

Recharging internal batteries

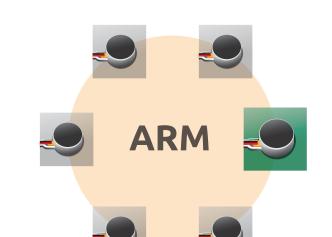
recording period.

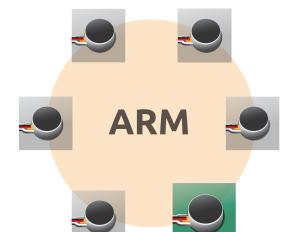
Adjusting the size of each band

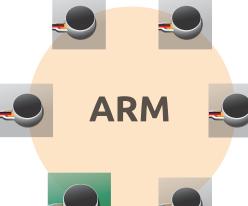
Dlay To play back a motion, the application compares the

saved (intended) position snapshot to the live (actual) position snapshot taken from the WAG Bands worn by the user. Comparing these two positions results in an error for each band that is translated into directed haptic feedback to guide the user to correct their motion.

WAG ARM BAND PRINTED CIRCUIT BOARD







user studies

The evaluation plan for the WAG System is in two parts:

These studies, in progress as of April 14, 2016, will evaluate:

Recording a new motion
 Editing a motion

future improvements

(1) The intuitiveness of navigating the software application while:

(2) The usefulness of vibration feedback for motion training

This project offers numerous expansion opportunities, including:

• Enabling motion file synchronization across multiple WAG Systems

• Streaming motion data from a trainer to a trainee for real-time feedback

Visually overlaying real-time position onto recorded motion

• Integrating respiration, blood-oxygen, and heart rate sensors

• Analyzing the effectiveness of the WAG System as a training tool

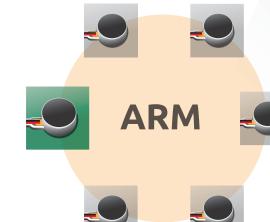
• Tracking user motion statistics to suggest improvements

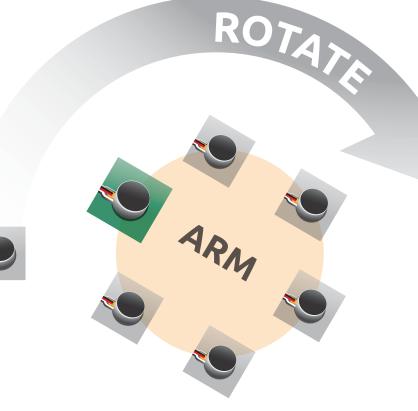
Adding hardware bands for the legs to include lower body motion training

(1) user studies for the software flow, and

(2) user studies on the complete system.

Opening a motion for playback



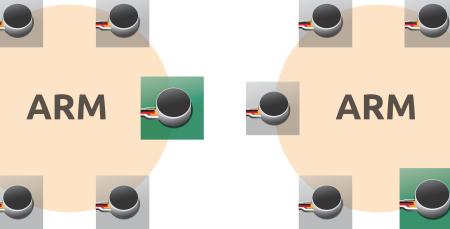


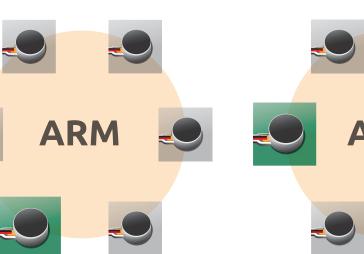
application collects snapshots of position information from

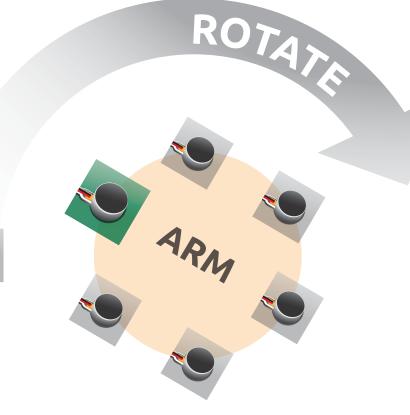
each of the 7 bands, at a regular time interval, over the

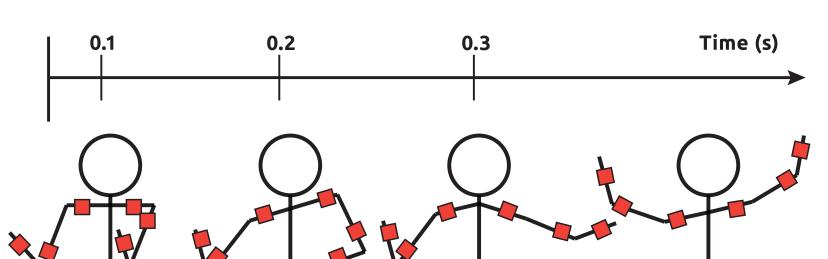


learn Each WAG Band generates a feedback signal consisting of a rotational component and a translational component. The band uses simultaneous vibrations for translational error and sequential vibrations for rotational error to apply the feedback signal to the six motors so the users can correct themselves in real time.



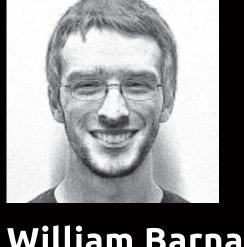






team suitup

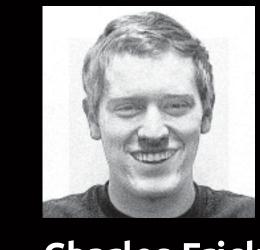




ROBOTICS ENGINEERING

William Barnard

Angular Error (for each band)



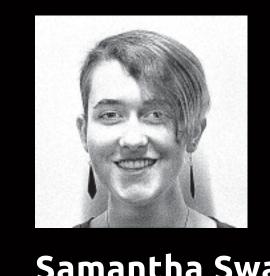
At this time, this project is competing as a finalist in the 2016 Intel Cornell Cup Competition.

notes

A provisional patent was filed through WPI on March 11, 2016.

Charles Frick ELECTRICAL AND COMPUTER ENGINEERING

ROBOTICS ENGINEERING



Samantha Swartz **COMPUTER SCIENCE ROBOTICS ENGINEERING**

acknowledgements

ROBOTICS ENGINEERING ADVISOR Professor Fred Looft ELECTRONICS AND SYSTEMS ENGINEERING ADVISOR Professor Hugh Lauer **COMPUTER SCIENCE ADVISOR**

Professor Mike Gennert

TAN Advisor Group **ENTREPRENEURIAL CRITIQUES** Shannon Cotter

ADMINISTRATIVE ASSISTANCE

Joe St. Germain **3D PRINTING** Todd Keiller INTELLECTUAL PROPERTY ADVISOR Fred Swartz **GRAPHICS DESIGNER Advanced Circuits**

Pololu

MOTOR DISCOUNT

ADVANCED **PCB MANUFACTURING SPONSORSHIP**



S.W.artz



Matthew Beardsley ROBOTICS ENGINEERING