



Movement smoothness during dynamic postural control to a static target differs between autistic and neurotypical children

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ABSTRACT

Autistic children and adults have known differences in motor performance, including postural instability and atypical gross motor control. Few studies have specifically tested dynamic postural control. This is the first study to quantify movement smoothness and its relationship to task performance during lateral dynamic postural control tasks in autism. We sought to test the hypothesis that autistic children would have less smooth movements to lateral static targets compared to neurotypical children, and that this difference would relate to specific movement strategies. We used camera-based motion-capture to measure spatiotemporal characteristics of lateral movement of a marker placed on the C7 vertebrae, and of markers comprising trunk and pelvis segments during a dynamic postural control task administered in an immersive virtual environment. We tested a sample of 15 autistic children and 11 age-matched neurotypical children. We quantified movement smoothness using dimensionless jerk cost. Autistic children exhibited more medial-lateral pelvic position range of motion compared to neurotypical children, and used a stepping strategy more often compared to neurotypical children. Autistic children also had higher jerk cost than neurotypical children for motion of the C7 marker. All participants had higher jerk cost for far targets than for near targets. Autistic children had longer trial durations than neurotypical children, and younger children had longer trial durations than older children across diagnostic groups. The stepping strategy observed more often in the autistic group likely contributed to jerk cost and reduced movement smoothness. This strategy is indicative of either an attempt to prevent an impending loss of balance, or an attempt to compensate for and recover from a loss of balance once it is detected. Implications of results are discussed, specifically with respect to anticipatory, feed-forward control of movement.

INTRODUCTION

Though not a current diagnostic feature of autism, motor differences have been noted both clinically and in research (for reviews, see Caçola et al., 2017; Heathcock et al., 2015; Lim et al., 2017; Ming et al., 2007). In some cases, autistic people meet criteria for a co-occurring diagnosis of Developmental Coordination Disorder (Green et al., 2009; Miller et al., 2021). Differences in perception of and responses to sensory input likely contribute to the core symptoms of ASD (Fulceri et al., 2019), including social communication (Cook, 2016;

Glazebrook, Elliott, & Szatmari, 2008; Leary & Hill, 1996), and may even rise to the level of a core feature or diagnostic specifier (Fournier et al., 2010; Leary & Hill, 1996; Whyatt & Craig, 2013).

Prior studies have identified motor differences in autistic compared to neurotypical participants during performance of gross motor tasks (Jansiewicz et al., 2006; Provost, Heimerl, & Lopez, 2007; Miller et al., 2021), postural stability tasks (Fournier et al., 2010; Miller et al., 2019; Minshew et al., 2004), and locomotion (Bugnariu et al., 2013; Hallett et al., 1993; Vernazza-Martin et al., 2005). However, the mechanisms underlying motor differences remain unclear. Imaging studies have also identified atypical neural activations in areas of the brain related to eye movement and visual processing (Brenner, Turner, & Müller, 2007; Luna et al., 2002; Takarae et al., 2007), and motor control (Mostofsky, Burgess, & Gidley Larson, 2007; Travers et al., 2017; Mosconi et al., 2015). It is possible that visuomotor integration mechanisms contribute to the broad range of motor differences observed in autism (Dowd et al., 2012; Miller et al., 2014; Williams, Whiten, & Singh, 2004; Mosconi et al., 2015; Wang et al., 2015).

A previous study established a relationship between smoothness of kinematic profiles and visual perception differences in autistic participants' goal directed reaching (Cook et al., 2013). Movement smoothness has previously been used as an index for motor performance in neurotypicality and neurodivergence (Ketcham et al., 2002; Platz et al., 1994; Rohrer et al., 2002; Teulings et al., 1997). Smoothness is frequently quantified as *jerk*—the derivative of acceleration with respect to time (Hogan & Sternad, 2009). Other measures (e.g., number of velocity peaks; Cirstea & Levin, 2000; Fetters & Todd, 1987) lack optimal sensitivity and robustness (Balasubramanian, Melendez-Calderon, & Burdet, 2012). The rationale for quantifying smoothness using jerk is rooted in the observation that many human movements are characterized by bell-shaped velocity curves (Cook, Blakemore, & Press, 2013; Flash & Hogan, 1985; Todorov & Jordan, 1998) and closely resemble trajectories predicted by minimum jerk and two-thirds power law equations (Flash & Hogan, 1985; Todorov & Jordan, 1998). Normalized jerk metrics have been used to show differences in smoothness of movements between neurotypical and neurodivergent populations (Hogan & Sternad, 2009). The advantage of normalizing jerk to a dimensionless value is that signals of different duration and amplitude can be compared (Hogan and Sternad 2009).

The aim of this study was to compare autistic and neurotypical children's dynamic postural control, quantified as the smoothness of goal-directed medial-lateral movements to a static target. Specifically, we assessed derivatives of time-series kinematic data, including

velocity, acceleration, and jerk. We hypothesized that smoothness would be significantly disrupted in autism, reflecting atypical motor control.

METHOD

The study protocol and informed consent/assent procedures were approved by the North Texas Regional Institutional Review Board. Informed consent/assent procedures were completed by participants and their guardian(s) as appropriate based on age and capacity.

Participants

Participants included 15 autistic children (Male=13, Female=2; $M_{Age}=10.47$ years, $SD_{Age}=1.77$ years) and 11 neurotypical children (Male=7, Female=4; $M_{Age}=8.91$ years, $SD_{Age}=1.58$ years).

Participants were recruited from schools, community organizations, clinics, and advocacy groups via face-to-face interactions, e-mail, and social media. Recruitment ads did not specifically solicit autistic participants with motor problems. Participants and their guardian(s) completed a developmental and medical history. Potential participants were excluded if they had a comorbid genetic or neurological disorder, seizure disorder, history of brain injury, structural brain abnormality, prior concussion with loss of consciousness, or coordination difficulties due to a general medical condition (e.g., cerebral palsy, hemiplegia, muscular dystrophy). Individuals taking medications known to significantly affect motor functioning (e.g., benzodiazepines, antipsychotics) were excluded, but given the comorbidity of attention disorders and prevalence of stimulant use in autism (DeFlippis & Wagner 2016), we did not exclude participants reporting stimulant use.

All autistic participants had a diagnosis assigned by a medical or educational professional based on the 4th or 5th edition of the Diagnostic and Statistical Manual of Mental Health Disorders (DSM; APA, 2000; 2013) and confirmed by the research team using the Autism Diagnostic Observation Schedule–Second Edition (ADOS-2; Lord et al., 2012). All participants had a non-verbal IQ score ≥ 70 confirmed by the research team using the Wechsler Abbreviated Scale of Intelligence–2nd edition (WASI-2; Wechsler, 2011). Participants in the neurotypical group had no prior history of developmental conditions and scored > 8 on the Social Communication Questionnaire (SCQ; Rutter, Bailey, & Lord, 2003), a conservative cutoff indicating no concern for autism.

Dynamic Postural Control Task

Participants performed a dynamic postural control task in an immersive virtual environment (see Miller, Bugnariu, Patterson, Wijayasinghe & Popa, 2017 for detailed description of apparatus). In this task, participants were instructed to move a user-controlled object (blue ball, 29.21 cm in diameter) into a static target area referred to as the *safe zone* (green box, 31.75 cm wide). The user-controlled object was controlled by medial-lateral movement of a marker placed on the participant's 7th cervical vertebrae (C7). The movement of the C7 marker was scaled by a factor of 5 when projected on the screen, such that a 1 cm change in the medial-lateral position of the C7 marker resulted in a 5 cm change of the user-controlled object.

Trials were classified as a "hit" if 70% of the user-controlled object was within the target area for 0.2 s. If 3 s elapsed without a successful hit, the safe zone disappeared. After each trial, the screen was then blank for 1 s after which a central fixation cross appeared for 600 ms, prompting the participant to return to the starting position. The safe zones were located on either side of the participant (left or right) and at either 26.8 cm or 13.4 cm (far or near) away from the starting location (center). Four instances of each of these safe zone locations (a total of 16) were displayed in the virtual environment in a randomized order. After the last safe zone disappeared, the task ended.

Data Collection and Processing

28 reflective markers were placed on participants' head, trunk, pelvis, and feet. Kinematic data were acquired from an 18-camera motion capture system at 120 Hz using Cortex software (Motion Analysis Corporation, Santa Rosa, CA, USA). Kinematic data were filtered using a fourth order low-pass Butterworth filter with cutoff frequency of 6 Hz. The filtered medial-lateral C7 position data was extracted from Cortex. Frontal plane trunk angle (trunk lean) and medial-lateral pelvis center-of-mass (COM) position were calculated using Visual3D (C-Motion, Inc., Germantown, MD, USA). Velocity, acceleration, and jerk profiles were calculated in MATLAB (Mathworks Inc., Natick, MA, USA) using first, second, and third order three-point derivatives, respective of the position and joint angle data. Each derivative profile was filtered with the same fourth order low-pass Butterworth filter with cutoff frequency of 6 Hz. For trials when the safe zone appeared on the left, each data point (position, velocity, acceleration, and jerk profiles) was multiplied by -1, so that right- and left-side safe zones could be pooled for analysis.

Trial duration was calculated as elapsed time from safe zone onset to offset (either due to a “hit” or because the maximum 3s had elapsed). Each position, velocity, acceleration, and jerk profile was resampled to 101 points to represent 0-100% of the trial and grouped by diagnosis (autistic, neurotypical) and target distance (near, far).

Movement smoothness was quantified as the natural logarithm of the normalized and integrated squared jerk of an entire trial (Equation 1), as in previous work (Dixon et al., 2018; Gulde & Hermsdörfer, 2018). The start and endpoint of a trial were defined as the safe zone onset and offset, respectively.

$$\log \text{ dimensionless jerk} = -\ln \left(\frac{(t_2 - t_1)^5}{(x(t_2) - x(t_1))^2} \int_{t_1}^{t_2} \ddot{x}(t)^2 dt \right) \quad (1)$$

Since trial duration was not held constant, and integrated squared jerk is sensitive to trial duration, it was important that this metric was normalized and converted to a dimensionless unit to make valid comparisons across trials (Hogan & Sternad, 2009). In addition, the natural logarithm brings the normalized and integrated squared jerk into the physiological range (Balasubramanian, Melendez-Calderon, & Burdet, 2012).

Data Analysis

Of the possible 416 trials available across the sample, 398 (95.7%) were included in analysis. Trials with durations shorter than 0.65 s were excluded because they were too short to represent volitional movement towards the target. These were either (1) trials in which the participant’s starting position was already inside the safe zone, or (2) trials in which the participant was already moving toward the safe zone at the start of the trial.

Data were analyzed in a series of generalized mixed-effects models using the lme4 package in R (version 4.1). Generalized linear mixed-effects models (GLMM) using Gamma distribution with a log link were used to regress trunk and pelvic range of motion (ROM) and jerk cost onto group (autistic, neurotypical), distance (near, far), and age (in months at the time of data collection) with a random intercept by participant. A GLMM using a binomial distribution with a logit link was used to regress the number of steps taken during a movement onto the fixed effects of group, distance, and age with a random intercept by participant. Effects were considered significant if $p < 0.05$, and b weights are reported in log or log odds scale, respectively.

Results

Range of Motion

Generalized linear mixed-effects models using Gamma distribution with a log link were used to regress trunk leaning range of motion (ROM) and medial-lateral ROM of the pelvis position onto the fixed effects of group, distance, and age with a random intercept by participant. Figure 1 presents time-series kinematic data for the C7 marker, the trunk segment, and the pelvis segment.

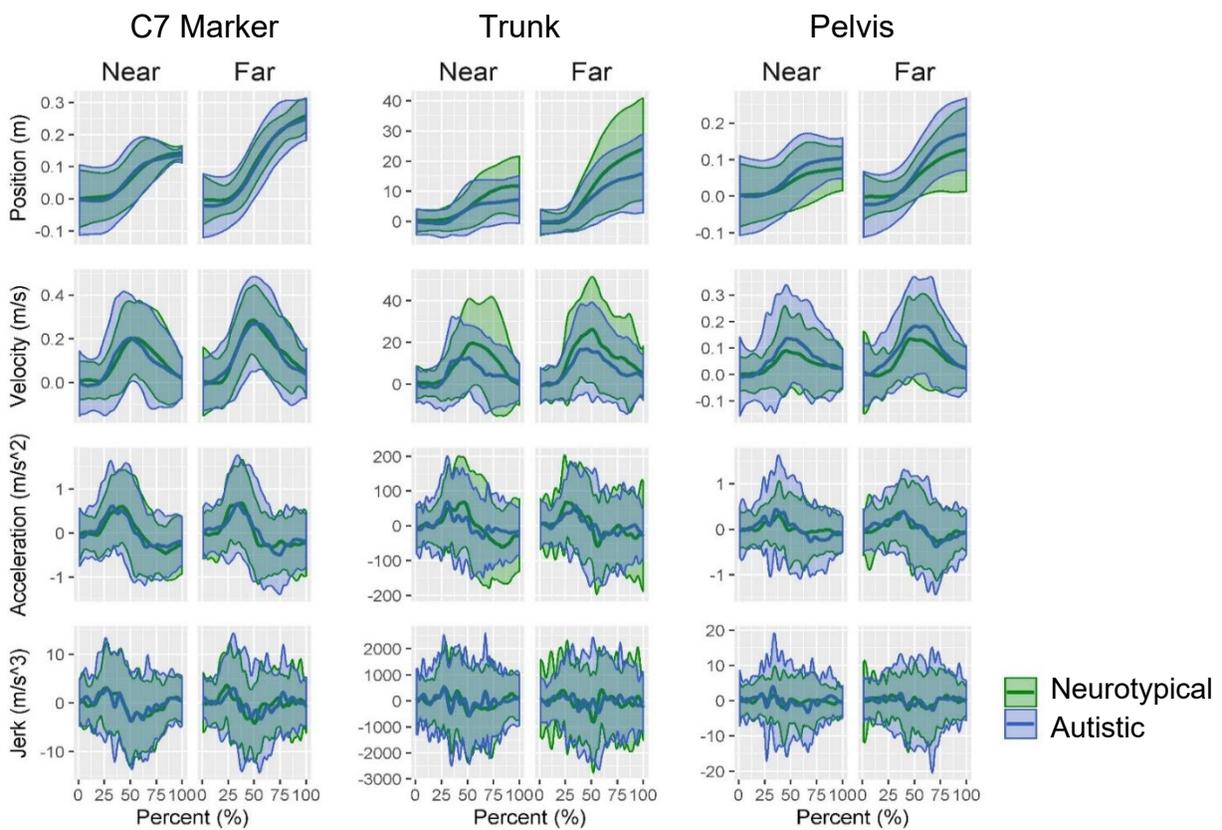


Figure 1. Spatiotemporal characteristics of autistic and neurotypical children's C7 marker, trunk segment, and pelvis segment movements to near and far targets from 0-100% of trial duration; mean (bold line) and standard deviation (lighter shading) of each derivative are displayed by group (autistic vs. neurotypical) and by distance to target (near vs. far).

Analysis of trunk leaning ROM yielded the expected main effect of distance ($Wald \chi^2_1=94.76, p<0.001$), such that trunk ROM was higher for far targets ($b=0.48, SE=0.05$), but no main effect of group ($Wald \chi^2_1=0.31, p=0.58$) or age ($Wald \chi^2_1=0.27, p=0.61$). Analysis of medial-lateral ROM of the pelvis position yielded a main effect of group ($Wald \chi^2_1=8.49, p=0.004$) such that pelvic ROM was greater for autistic children ($b=0.72, SE=0.25$), a main effect of age ($Wald \chi^2_1=3.88, p=0.049$), such that older participants had lower pelvic ROM ($b=-0.23, SE=0.12$). There was also a main effect of distance ($Wald \chi^2_1=17.42, p<0.001$), such that pelvic ROM was greater for far targets ($b=0.35, SE=0.09$). There were no significant interaction effects for trunk or pelvic ROM.

Movement Smoothness

C7 Marker.

The GLMM analysis for jerk cost of the C7 marker yielded main effects of group ($Wald \chi^2_1=4.02, p=0.045$; Figure 2), such that autistic children had a higher jerk cost than neurotypical children ($b=0.12, SE=0.06$), and distance ($Wald \chi^2_1=6.51, p=0.011$; Figure 2), such that movements to far targets were less smooth than movements to near targets ($b=0.047, SE=0.02$). There was not a main effect of age ($Wald \chi^2_1=1.89, p=0.17$), nor were there any significant interaction effects.

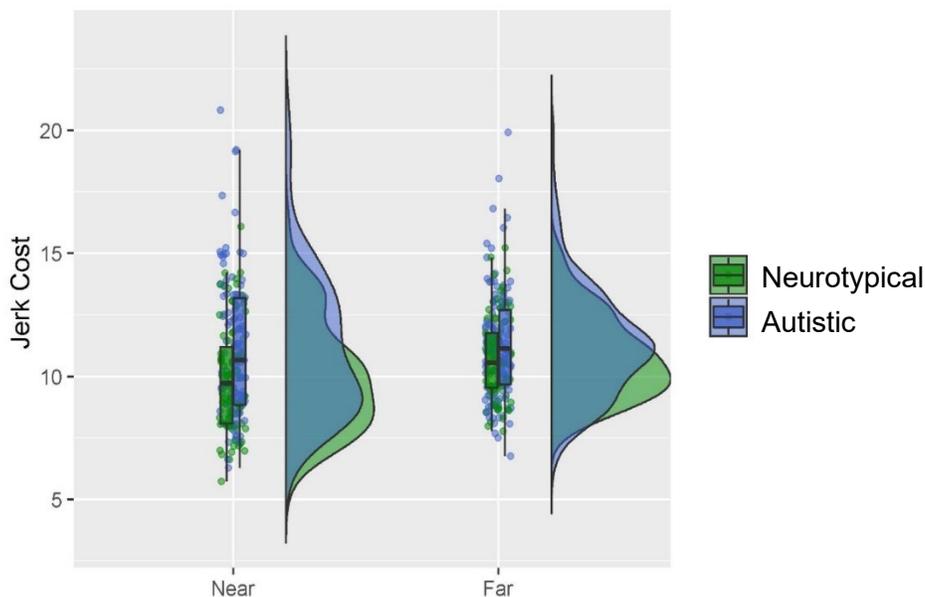


Figure 2. Jerk cost of autistic and neurotypical children's C7 marker movements to near and far targets.

Trunk Segment.

The GLMM analysis for jerk cost of the C7 marker yielded main effects of group ($Wald \chi^2_1=4.02, p=0.045$; Figure 2), such that autistic children had a higher jerk cost than neurotypical children ($b=0.12, SE=0.06$), and distance ($Wald \chi^2_1=6.51, p=0.011$; Figure 2), such that movements to far targets were less smooth than movements to near targets ($b=0.047, SE=0.02$). There was not a main effect of age ($Wald \chi^2_1=1.89, p=0.17$), nor were there any significant interaction effects.

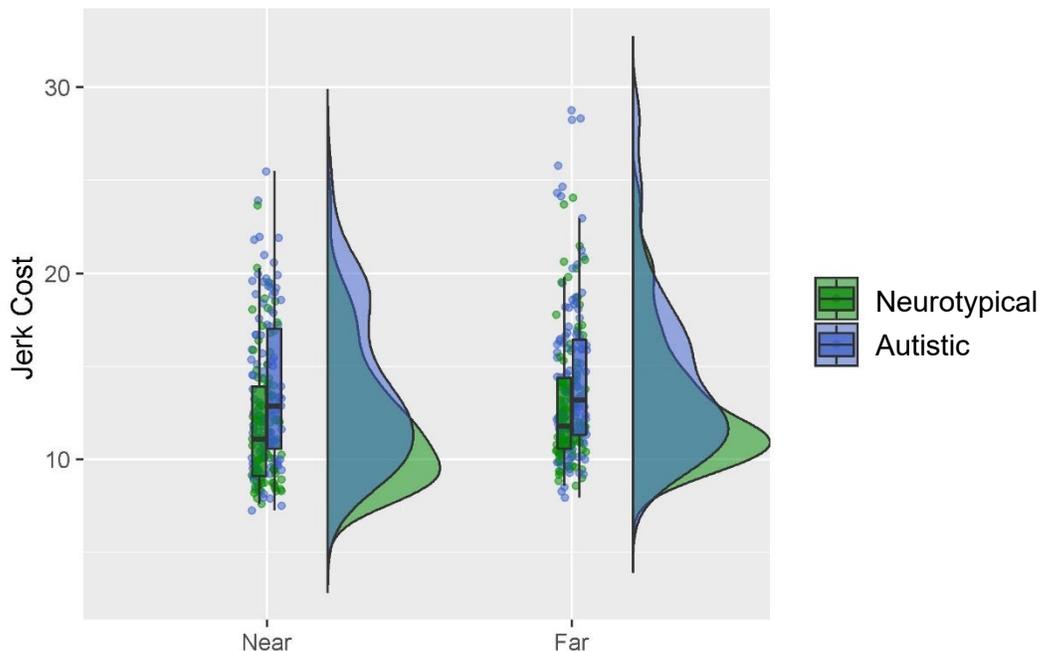


Figure 3. Jerk cost of autistic and neurotypical children's trunk segment movements to near and far targets.

Pelvis Segment.

The GLMM analysis for jerk cost of the pelvis segment yielded a main effect of distance ($Wald \chi^2_1=20.94, p<0.0001$; Figure 4), such that movements to far targets were less smooth than movements to near targets ($b=0.08, SE=0.02$). There was not a main effect of age ($Wald \chi^2_1=2.33, p=0.13$) or group ($Wald \chi^2_1=0.47, p=0.49$), nor were there any significant interaction effects.

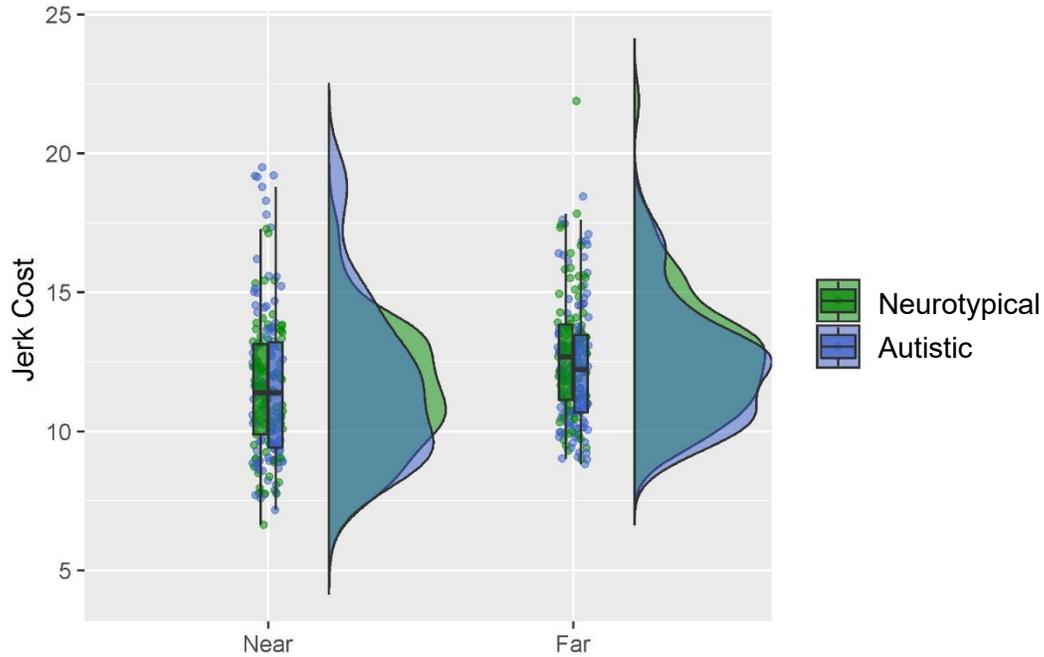


Figure 4. Jerk cost of autistic and neurotypical children’s pelvis segment movements to near and far targets.

Trial Duration.

The GLMM analysis for trial duration yielded main effects of group ($Wald \chi^2_1=5.64$, $p=0.018$; Figure 5), such that autistic children took more time to get to the safe zone than neurotypical children ($b=0.15$, $SE=0.06$), distance ($Wald \chi^2_1=69.0$, $p<0.0001$; Figure 5), such that movements to far targets took more time than movements to near targets ($b=0.24$), and age ($Wald \chi^2_1=6.26$, $p=0.012$; Figure 5), such that older participants reached the target more quickly than younger participants ($b=-0.08$, $SE=0.03$).

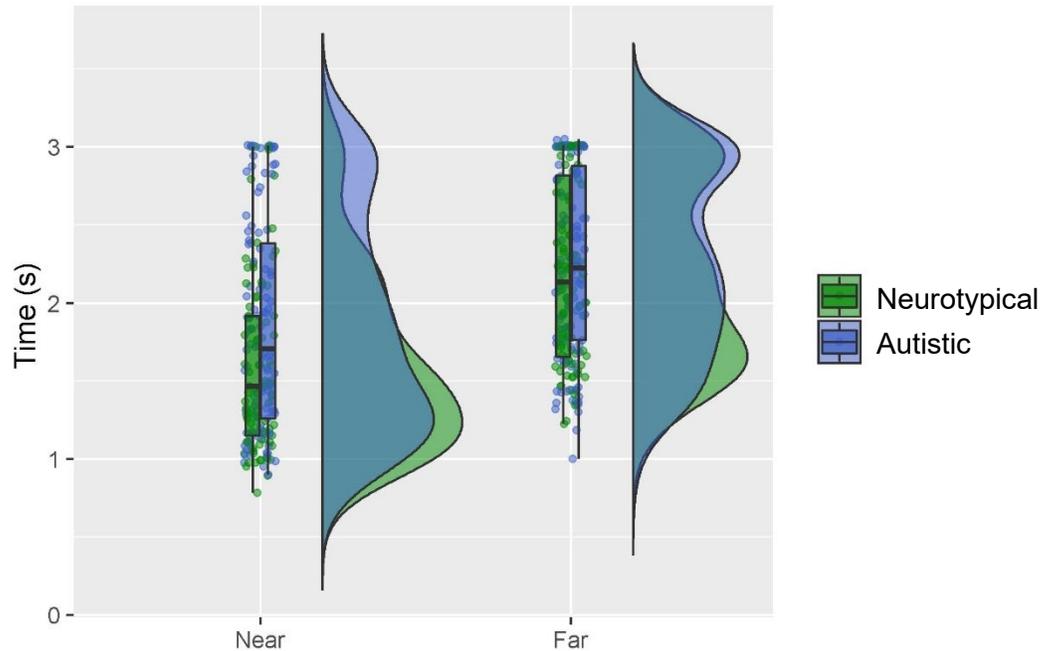


Figure 5. Trial duration for autistic and neurotypical children's movements to near and far targets.

Likelihood of Taking a Step.

The GLMM analysis for log odds of taking a step yielded a main effect of group ($Wald \chi^2_1=4.52$ $p=0.033$; Figure 6), such that autistic children took a step during a trial more frequently relative to neurotypical children ($b=2.40$, $SE=1.13$), and distance ($Wald \chi^2_1=12.17$, $p=0.0005$; Figure 6), such that participants were more likely to take a step towards a far target than a near target ($b=1.07$, $SE=0.31$). There was not a significant main effect of age ($Wald \chi^2_1=1.05$, $p=0.059$), nor were there any significant interaction effects.

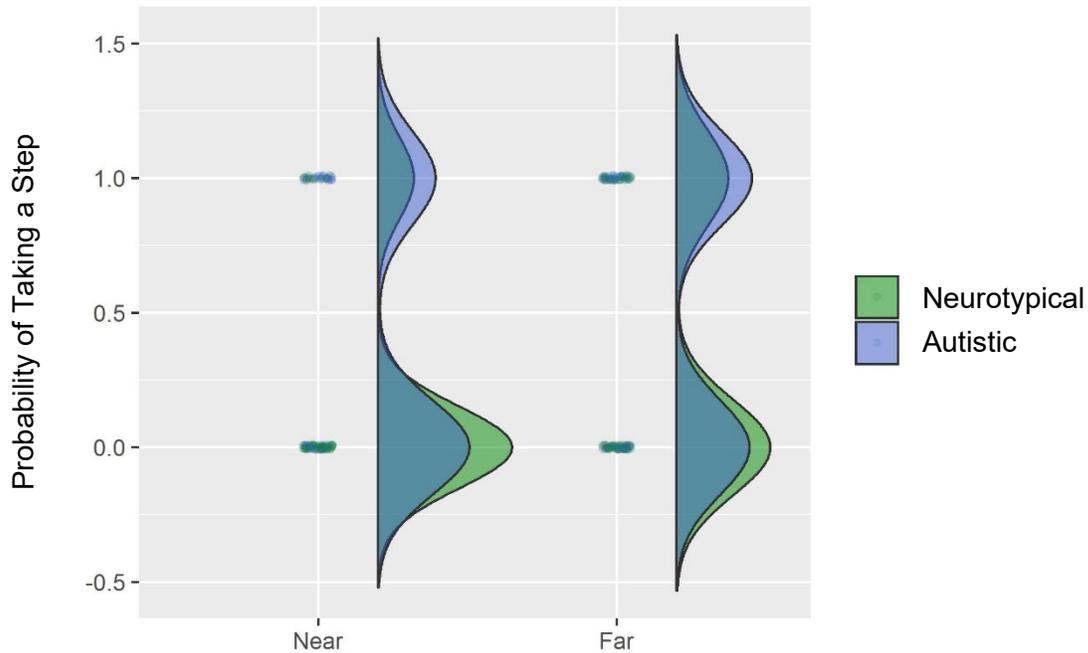


Figure 6. Results of a generalized linear mixed effects model using a binomial distribution with a logit link regressing the number of steps taken during a movement onto the fixed effects of group, distance, and age with a random intercept by participant showed that neurotypical children took fewer steps during the task compared to autistic children.

Discussion

This is the first study to quantify differences in movement smoothness between autistic and neurotypical children during goal-directed leaning. Consistent with a prior study of gait smoothness (Nobile et al., 2011), autistic children in our sample exhibited higher jerk cost during goal-directed movement. Because participants were not given specific instructions about the mechanism of action for the user-controlled ball, they had to formulate their own movement strategy.

Participants generally adopted one of three strategies: 1) leaning at the trunk while keeping feet and lower body stationary, 2) moving the entire body by stepping, or 3) a mixture of both. For safe zones in far (versus near) locations, both groups exhibited jerkier movements, longer trial durations, and were more likely to take a step to maintain balance. This suggests that coordinating movements over a larger distance posed a greater challenge to both groups.

This is consistent with previous studies showing that movement duration is scaled by movement amplitude, and smoothness decreases as duration increases (Salmond, Davidson, & Charles, 2017; Ketcham et al., 2002).

Analysis of trunk leaning and medial-lateral position of the pelvis revealed that although trunk leaning ROM did not statistically differ between neurotypical and autistic children, medial-lateral pelvic ROM was significantly greater in the autistic group. Additionally, autistic children were more likely to take a step during a trial than neurotypical children. This demonstrates that autistic children relied more heavily on moving their entire body, rather than on isolating trunk movements, to reach the safe zone.

Leaning (versus stepping) to a lateral target requires coordination of fewer degrees of freedom, and may therefore be a more efficient strategy to produce smooth movements. However, increased trunk ROM places greater demand on core stabilizing muscles. Others have observed that autistic children have reduced core strength (Kern et al., 2011), which may explain heavier reliance on whole body movements (i.e., lateral stepping). Avoiding core muscle engagement may produce atypical and jerky movements as observed in the present study, or low-acceleration swaying movements when matching oscillating dynamic targets as we have previously reported (Miller et al., 2019). Examination of anticipatory and reactive muscle activity may help to explain why autistic individuals appear to adopt different strategies under varying task conditions.

Interestingly, despite higher overall jerk cost, jerk cost in intermediate joint and segment trajectories (trunk leaning and medial-lateral pelvis position) was not significantly higher for autistic children. This suggests that autistic children may exhibit only slightly jerkier movements of isolated segments, but when coordinating multiple joints to achieve a task, the jerkiness of the overall movement is exacerbated. Motor coordination is influenced by several factors including sensory processing, motor planning, and muscle activations. Previous studies demonstrated that some or all of these features may be different in autism (e.g., Cook et al., 2013; Dowd et al., 2012; Glazebrook et al., 2008; Luna et al., 2002; Mosconi et al., 2015; Mostofsky et al., 2007). Future work is needed to assess how autistic people acquire, process, and integrate sensory information to support planning, execution, and modification of goal-directed movements.

In our study, autistic children appeared to rely less on feed-forward information, often initiating movements and accelerating toward the target before sufficient visual intake and processing could occur. This may reflect anticipatory differences (Schmitz et al., 2003), or a learned response to a lifetime of experiences with atypical visual processing (Sharer et al.,

2015) in turn forcing over-reliance on feed-back information after movement initiation. This approach is associated with reduced movement smoothness and efficiency (Liu & Todorov, 2007), consistent with our results. Over-reliance on feed-back control (as opposed to stochastic optimal control) is also a more effortful, on-line processing approach (Todorov & Jordan, 2002), potentially contributing to the longer trial durations we observed.

Conclusion

While movement smoothness has not previously been a key variable of interest in autism research, our results demonstrate that it is related to both the motor strategy selected for a given task, and the efficiency with which that task is performed. Accuracy, efficiency, and flexibility in dynamic postural control are necessary for functional mobility and mitigation of fall risk. They are also important determinants of how effortful and fatiguing a motor task is, and thus relate to quality of life. It is important to characterize the mechanisms underlying postural control and the impact of movement smoothness on functional mobility and fall risk in autism. In doing so, we will be better equipped to develop accommodations and interventions that support autistic individuals' ability to move more efficiently, safely, and comfortably

Contributions

Contributed to conception and design: HLM, RMP, NLB

Contributed to acquisition of data: HLM, GMS

Contributed to analysis and interpretation of data: TNT, HLM, NEF, RMP, NLB

Drafted and/or revised the article: HLM, TNT, NEF

Approved the submitted version for publication: HLM, TNT, NEF, GMS, RMP, NLB

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Data and Supplementary Material Accessibility

The data for this paper are currently in the process of being transferred from one university to another. As there are ongoing discussions about the rights and obligations for this dataset, it cannot be shared at this time.

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APPENDIX

Participant Instructions & Feedback

Participants heard and saw the following instructions with embedded visual examples of the user-controlled object and the safe zone on the screen:

“In this game, you will see a blue ball on the screen. This is your ball. When you move your body, your ball will move too. This is a green safe zone. Move your body to get your ball in the green safe zone. Move as fast as you can! Sometimes, the safe zone is in a different place. Try to stay in the safe zone!”

Participants were not given specific information about the control mechanism of the user-controlled object, the locations of the safe zones, or hit criteria. After a successful hit, virtual fireworks and a sound signaled success. If 3 s elapsed without a successful hit, the safe zone disappeared and a thumping sound signaled failure.

AUTHOR NOTE

Out of respect for preferences expressed by many autistic self-advocates in our studies and in the community, we have chosen to use identity-first (rather than person-first) language throughout this manuscript. In doing so, it is not our intention to diminish or invalidate the preferences or perspectives of those who prefer person-first language. We continue to welcome feedback on ways that we can effectively partner with the autistic community to advocate for respect, acceptance, inclusion, and representation in research.