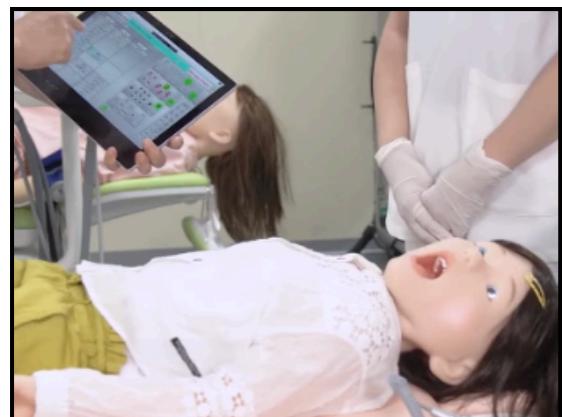




## Current pain synthesis methods for patient robots are not automatic

Dental Robot Simulator



©2025 tmsuk Pedia\_roid

General Patient Robot Simulator



Robot HAL® S3201

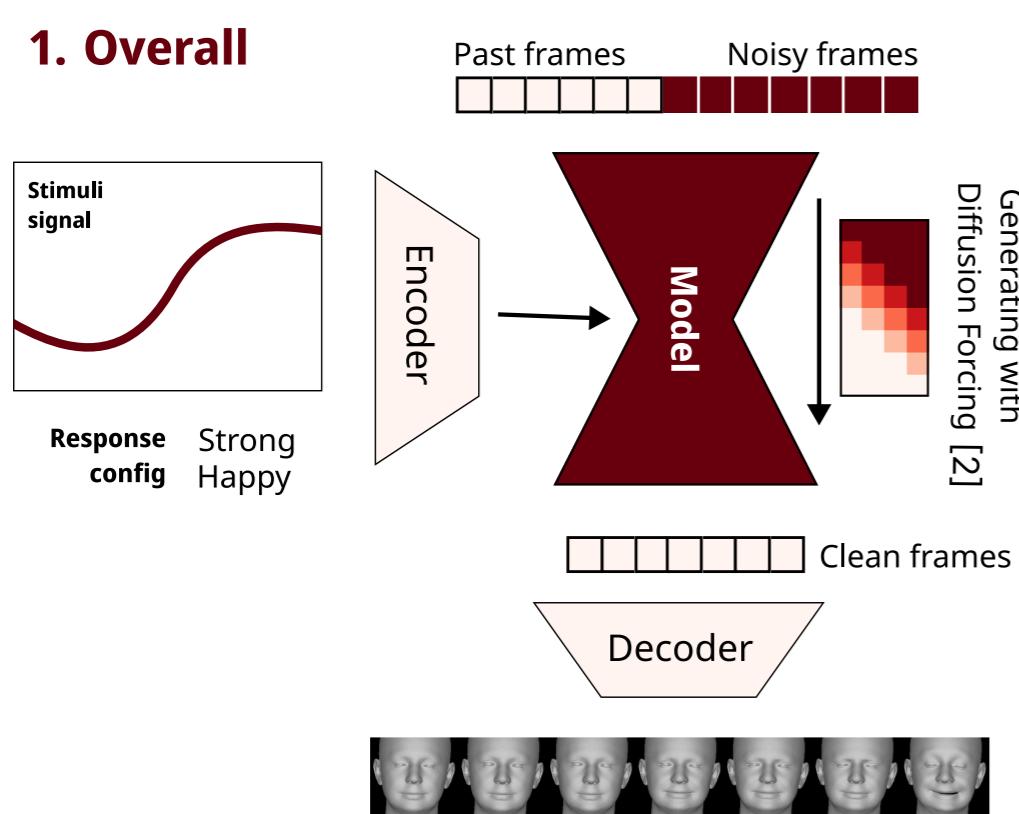
The current patient robots in the market have limited and static emotional expressions.

	Classify	Synthesize	Rule-based	Learning-based
Moosaei et al (2017)	✓	✓		
Huang et al (2019)	✓			✓
Haque et al (2018)	✓			✓
Lee et al (2021)	✓	✓		
<b>This method</b>	★		★	★

To the best of our knowledge, we are the first to tackle pain synthesis with a learning-based approach, which aims to make more realistic patient robots.

## Autoregressively and Continuously Generate Reaction Sequences

### 1. Overall



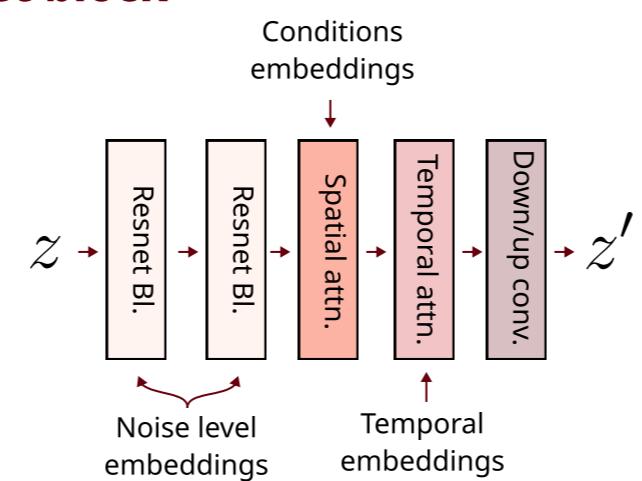
We train PainDiffusion on the Biobid Heatpain Database [1] with Elucidated Diffusion objective [3].

$$\mathbb{E}_{y \sim p_{\text{data}}, n \sim \mathcal{N}(0, \sigma^2)} \left[ \|y_{\text{pred}} - y_{\text{target}}\|_2^2 \right]$$

$$y_{\text{pred}} = F_{\theta} \left( c_{\text{in}}(\sigma) \cdot (y + n), c_{\text{noise}}(\sigma) \right)$$

$$y_{\text{target}} = \frac{1}{c_{\text{out}}(\sigma)} \left( y - c_{\text{skip}}(\sigma) \cdot (y + n) \right)$$

### 2. Unet block

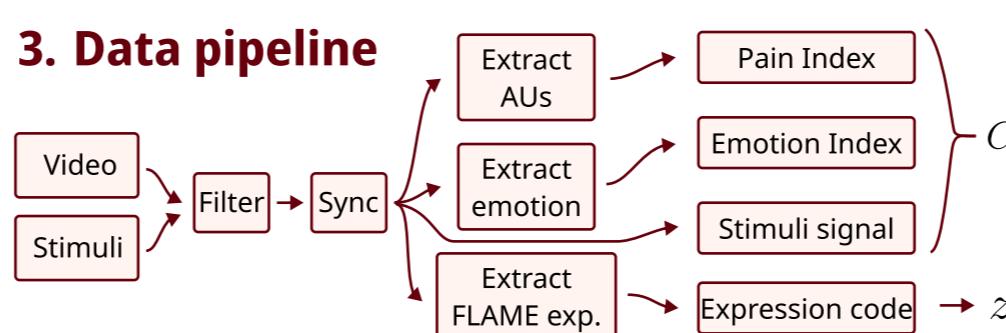


Both noise level and temporal embeddings are from sinusoidal positional encoding to add *positional information in both noise dimension and time dimension*.

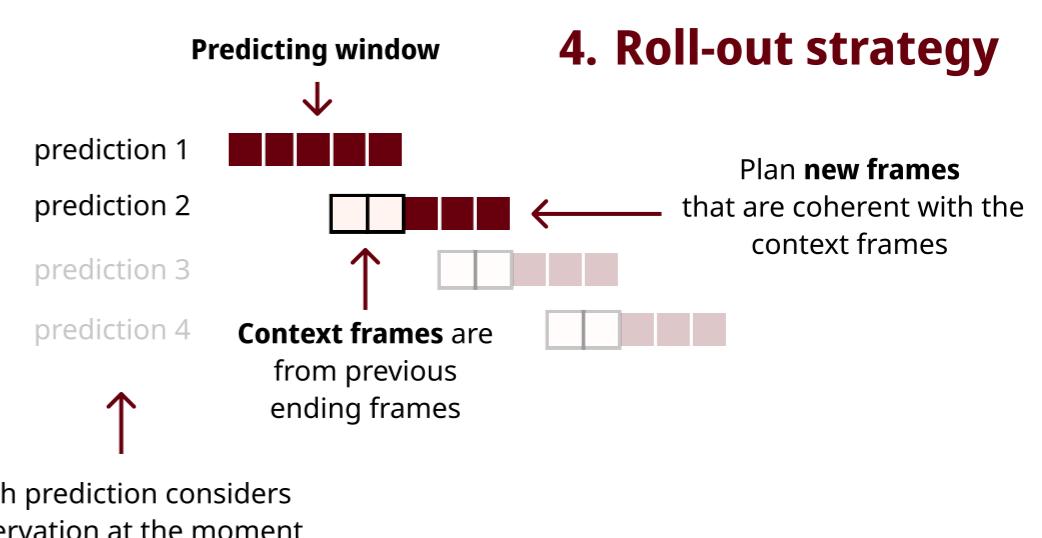
To flexibly tune the influence of each controlling signal we use a fine-grain version of classifier-free guidance in inference time.

$$\hat{z} = \left( 1 + \sum_{c \in C} \lambda_c \right) \cdot F_{\theta}(z, t, C) - \sum_{c \in C} \lambda_c \cdot F_{\theta}(z, t, C|_{c=0})$$

### 3. Data pipeline

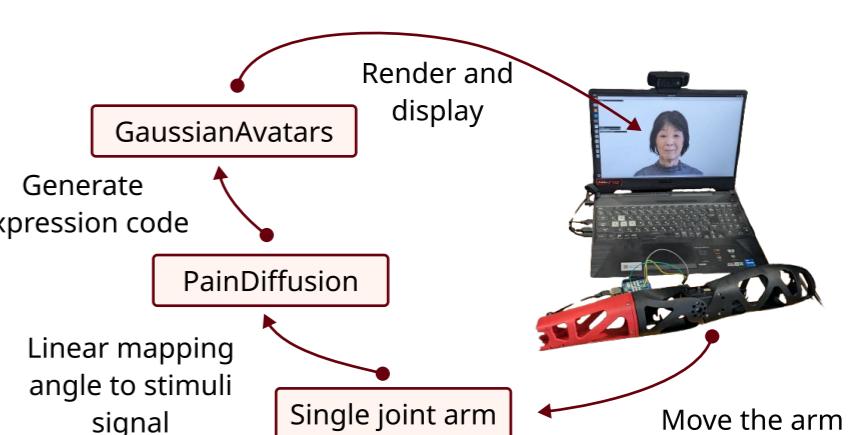


### 4. Roll-out strategy



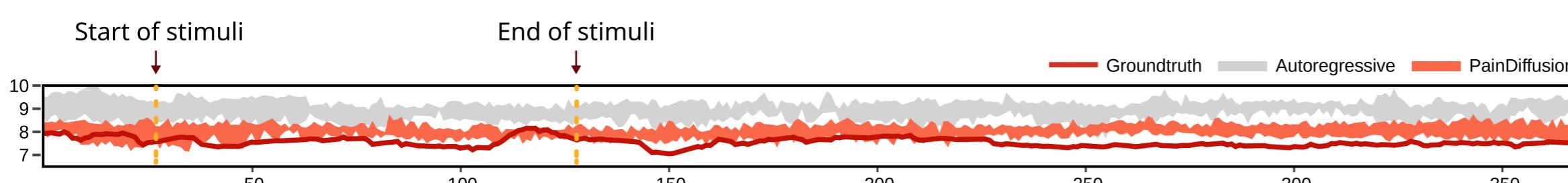
The context frames are added with *little noise level* to give more *freedom in predicting the future frames* while the future frames start from totally noise. The ratio of context frames and the length of the predicting window will affect how fast the model plan new frames.

### 5. Elbow range of motion exercise

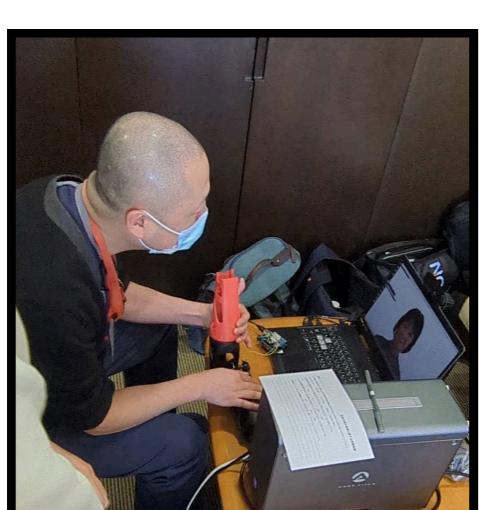


## PainDiffusion outperforms the autoregressive discretization method

We run 5 predictions to create the range of graph, the pain index signal from the ground truth recording falls within the predicted range of PainDiffusion while autoregressive baseline is higher.

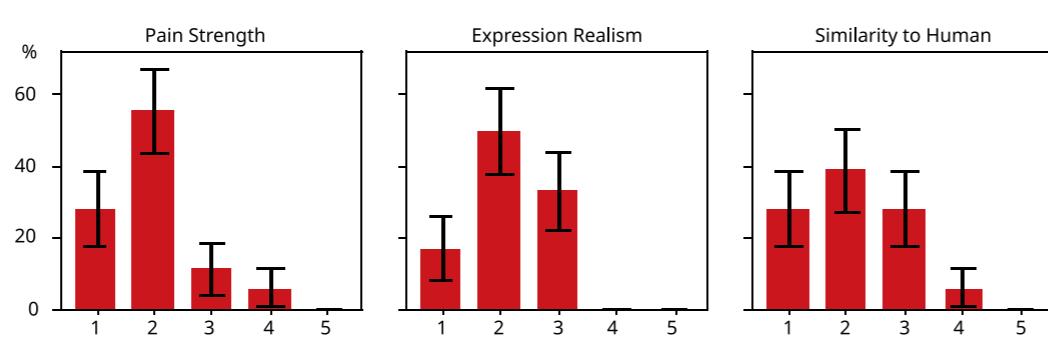


## Experts chose PainDiffusion 31% of the time in the video preference test

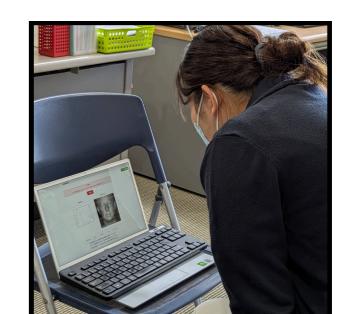
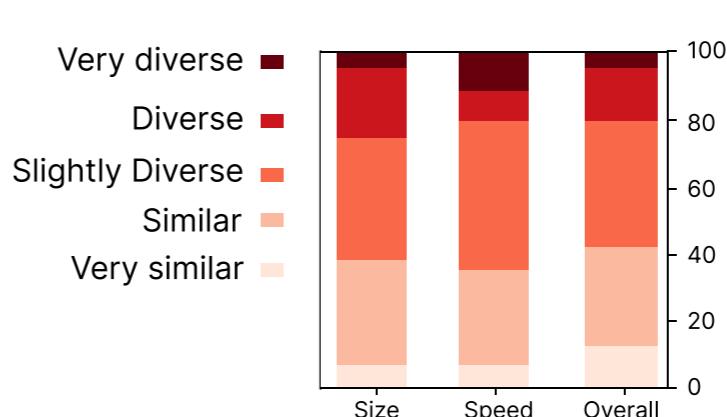


### Expressions against stimuli signal is quite real

We asked clinicians to practice rehabilitation elbow range of motion exercise on a single joint arm then rate the expression of the virtual avatar.

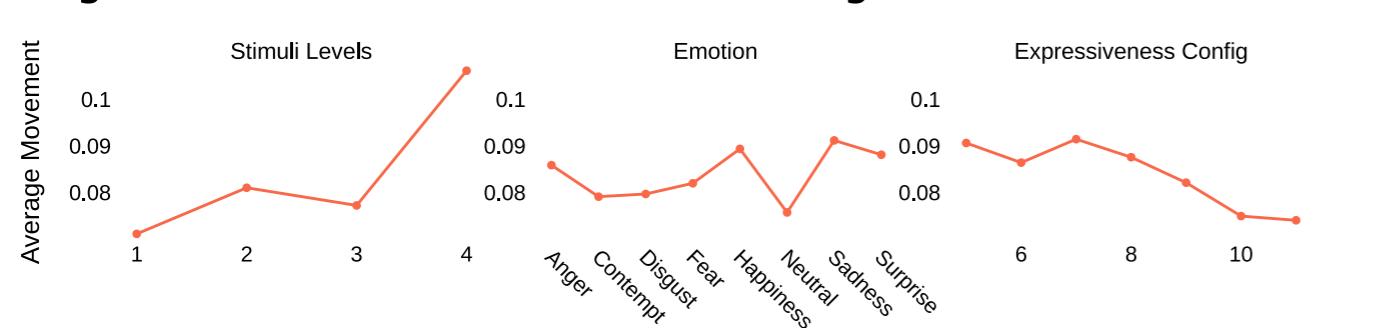


### Diversity of motion rated by clinicians

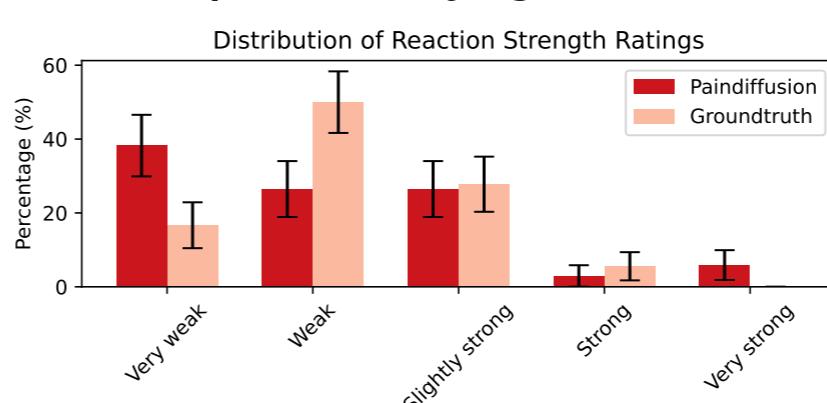


Preference test is between PainDiffusion and groundtruth.

### Magnitude of avatar movement across configurations



### Real examples are also judged as weak



### Further insights from clinicians

1. A *calibrated baseline* is needed for better assessing the expression.
2. Cultural elements (e.g. patient record) are necessary to make a more realistic pain expression model.