

# The Expected Utility of Movement

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## INTRODUCTION

Our survival depends on our ability to act effectively, maximizing the chances of achieving our movement goals. In the course of a day we make many movements, each of which can be carried out in a variety of ways. Shall I reach for that wine glass quickly or slowly? Shall I approach from the right or left? Movement planning is a form of decision making as we choose one of many possible movement strategies to accomplish any given movement goal. It is important for us to make these “motor decisions” rapidly and well. In this chapter, we consider how movements are planned and show that a certain class of movement-planning problems is mathematically equivalent to a

choice among lotteries in decision making under risk or ambiguity (see also Trommershäuser *et al.*, 2006a). This analogy allows us to examine movement planning from a new perspective, that of the ideal economic movement planner. It also allows us to contrast how we make decisions in two very different modalities; planning of movement, and traditional economic decision making.

We review our previous work on movement-planning under risk, in which subjects are generally found to be very good at choosing motor strategies that come close to maximizing expected gain – a result that is in contrast with that found with paper-and-pencil decision-making tasks. We discuss the implications of these different behavioral outcomes, noting the

evident differences between the sources of uncertainty and how information about uncertainty is acquired in motor and economic tasks. We finally review the evidence concerning the neural coding of probability, expected movement error, and expected gain in movement under risk (see also Chapters 23, 30, and 32). We begin, however, with a brief review of previous work on how biological organisms plan movement.

## MOVEMENT PLANNING AS OPTIMIZATION

In planning a movement, the brain has to select one of many possible movement plans or strategies. The result of executing a movement strategy is an actual trajectory, and it is evidently desirable that the choice of strategy satisfies the demands of the particular task and also minimizes “wear and tear” on the organism.

Typical research in the field of human motor control combines theoretical and experimental approaches. For example, a participant in a motor control experiment might perform simple reaching movements to a target, often constrained to two dimensions – for example, along the top of a table (Figure 8.1a). The recorded movement trajectories are compared with the predictions of a computational model mimicking the conditions of the experiment. Early approaches to modeling movement planning take the form of an optimization problem in which the cost function to be minimized is biomechanical and the optimization goal is to minimize some measure of stress on the muscles and joints. These models differ primarily in the choice of the cost function.

### Movement Planning Optimizing Biomechanical Constraints

Possible biomechanical cost functions include measures of joint mobility (Soechting and Lacquaniti, 1981; Kaminsky and Gentile, 1986), muscle tension changes (Dornay *et al.*, 1996), mean squared rate of change of acceleration (Flash and Hogan, 1985), mean torque change (Uno *et al.*, 1989), total energy expenditure (Alexander, 1997), and peak work (Soechting *et al.*, 1995). The outcome of applying these models is typically a single, deterministic trajectory that optimizes the tradeoff between the goal of the movement and the biomechanical costs for the organism. These models are successful in explaining the human ability to adapt to forces applied during movement execution

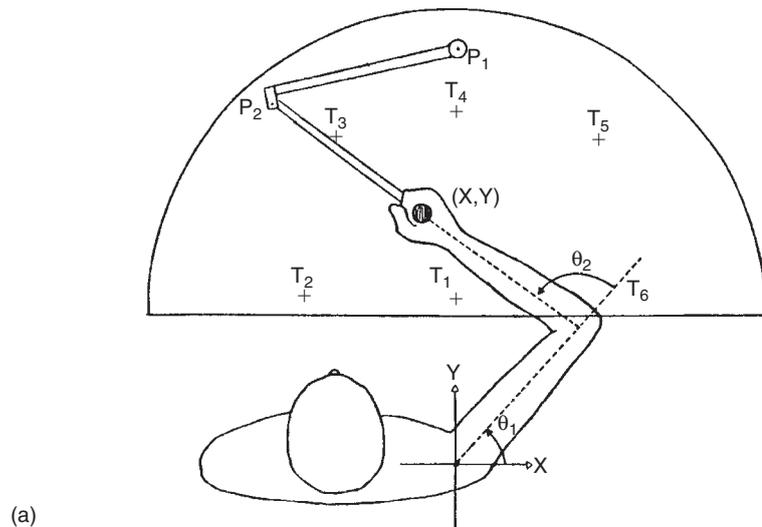
(Burdet *et al.*, 2001; Franklin *et al.*, 2007). Although this wide variety of cost functions has been employed, nearly all have successfully modeled reaching movements as following a nearly straight path with a bell-shaped velocity profile (Figure 8.1). A combination of biomechanical constraints was demonstrated by Cuijpers *et al.* (2004), who showed that humans will grasp an elliptical cylinder along either its major or its minor axis, resulting in a stable grip, but will tend to choose the axis closer to that used for circular cylinders (i.e., the grasp that is more comfortable).

### Compensation for Noise and Uncertainty

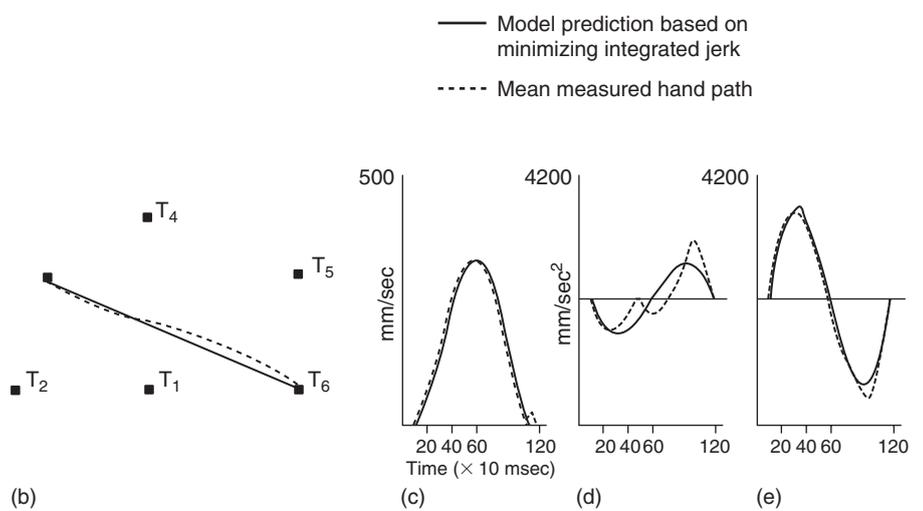
The models just described yield single deterministic trajectories that do not take into account the possible consequences of motor errors due to noise in the motor system. Consider two movement plans for a reach toward a target. The first involves maximal acceleration toward the target for half the reach, and maximal deceleration to come to a halt at the target. The second has a smooth acceleration/deceleration profile. We could consider the biomechanical costs associated with the two movements, but we can also characterize the two movements in terms of an external criterion of success: which is more likely to hit the target? In moving from the purely internal criterion of success (minimizing biomechanical costs) to an external measure, we change the nature of the movement-planning problem and its solution.

Figure 8.2 shows two movement plans, in this case for a 10° deg saccadic eye movement, both of which take the same amount of time to arrive, on average, at the identical target location (Harris and Wolpert, 1998). The two planned movements differ in how force is distributed along the reach. Movement 1 (Figure 8.2, dashed curves) begins with an explosive burst of force, rapidly rotating the eye toward the target, and ends with an equal but opposite explosive burst as the eye approaches the target. Such an extreme use of force is often referred to as “bang-bang” control. Movement 2 (solid curves) has a smooth acceleration profile, with gradual acceleration during the first half of the reach and deceleration during the second.

Uncertainty in the motor system originates from noisy neural control signals that lead to variable motor output. The noise is signal-dependent; larger control signals lead to larger variability in motor outcome (Harris and Wolpert, 1998). Thus, faster movements, which require larger control signals, are more variable, resulting in the well-known speed-accuracy tradeoff. Modeling such signal-dependent noise, Harris and Wolpert (1998) found that the movement that



**FIGURE 8.1** Example of a model of movement planning as optimization of a biomechanical constraint. (a) Subjects moved a manipulandum between various target positions (labeled T1, ..., T6). (b) Hand path toward one example target. (c) Hand velocity. (d-e) Acceleration in the *x* (panel (d)) and *y* (panel (e)) directions. Dashed curves, mean measured hand path; solid curves, hand paths predicted by a model that minimized integrated jerk (rate of change of acceleration). The measured hand path shows a typical smoothly curved trajectory with a bell-shaped velocity profile. The minimum-jerk model (dashed curves) does a reasonable job of predicting movement kinematics. Reprinted from Flash and Hogan (1985), with permission.

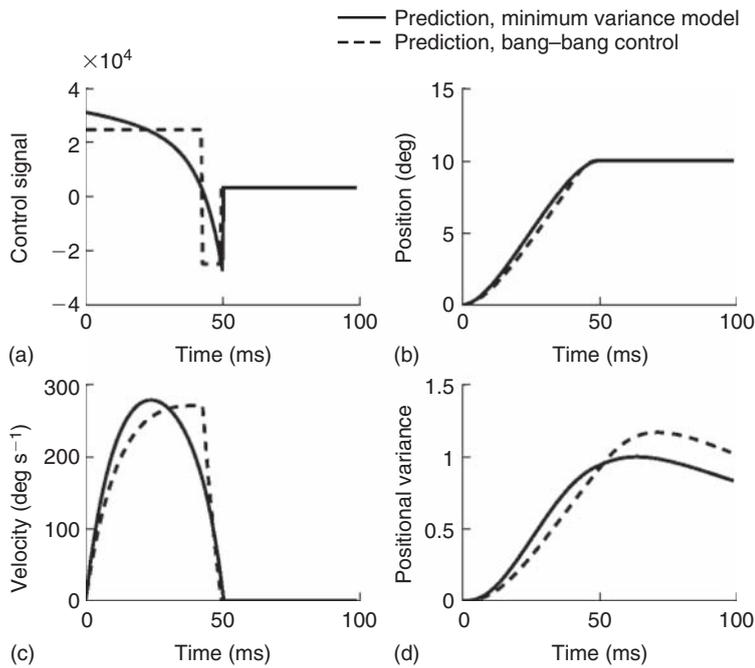


minimizes positional variance at the end of the movement, subject to the two constraints of movement duration and mean endpoint, is Movement 2 (solid curves).

Recent experimental work concerned with the planning and execution of speeded eye and arm movements indicates that the complex sequences of neural events that underlie voluntary movements are selected so as to minimize movement error (Sabes and Jordan, 1997; Harris and Wolpert, 1998; Todorov, 2004). Note that this approach is based on the notion that the endpoint variability is a consequence of the “biological noise” in the motor control system, and therefore unavoidable.

Following the observation that movements are corrupted by considerable motor noise and do not always follow the same deterministic trajectory, Harris and Wolpert (1998) suggested that movement trajectories are selected to minimize the variance of the final eye

or arm position. They proposed that the underlying determinant of trajectory planning is the minimization of the noise in the neural control signal that activates the muscles during the execution of a motor command and in the post-movement period. In their model, the final arm or eye position is computed as a function of a (deterministic) biomechanical expression and a noisy neural signal, where the noise increases with the magnitude of the neural signal (Figure 8.2). According to the model of Harris and Wolpert (1998), the planned trajectory of the eye and arm is chosen to minimize variance in the endpoint of the movement. The idea behind this approach is that the variability in the final position of a saccade or pointing movement is the result of the accumulated deviations of the executed trajectory from the planned trajectory over the duration of the movement. Horizontal saccadic eye movements, hand paths for a set of point-to-point



**FIGURE 8.2** Predictions of a model of a  $10^\circ$ , 50-ms eye movement with signal-dependent noise. Dashed curves, the result of “bang-bang” control in which nearly maximum acceleration is applied throughout the movement until just prior to movement completion, at which point the eye is quickly brought to a stop; solid curves, movement achieving minimum positional variance at the end of the movement. The minimum-variance model predicts a bell-shaped velocity profile and results in substantially lower end-point variance. (a) Control signal; (b) position; (c) velocity; (d) positional variance.

Reprinted from Harris and Wolpert (1998), with permission.

movements (Harris and Wolpert, 1998), and the movement trajectories measured in an obstacle-avoidance task (Hamilton and Wolpert, 2002) are all consistent with predictions of the model.

In a similar approach, Sabes and Jordan (1997) studied the contribution of kinematic and dynamic properties of the arm to movement planning. Subjects moved their hands between pairs of targets, avoiding an obstacle along the path. To carry out this task rapidly while avoiding the obstacle, subjects should choose a trajectory so that the direction from the obstacle to the trajectory at its nearest approach is one for which movement variability is minimal. Given the difficulty of measuring two-dimensional movement variability during a reach, the authors instead modeled the sensitivity of the arm in various directions and at various positions in the workspace. They defined three sensitivity measures (kinematic, inertial, and elastic), each of which provided predictions of the point of closest approach to the obstacle that was most safe. The data were in qualitative agreement with the predictions of all three sensitivity measures, and best predicted by their inertial sensitivity model (*mobility*).

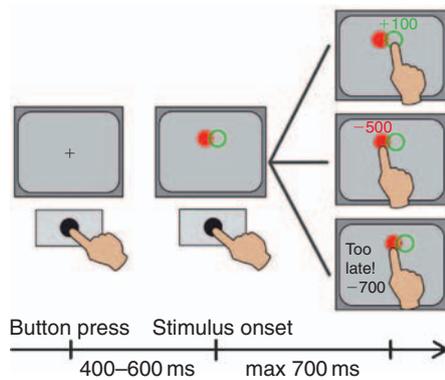
### Optimization of the Consequences of Movement

So far, we have considered the costs of movement in terms of biomechanical costs (energy, wear and tear) and movement accuracy. Both these criteria for movement planning may be used by humans for planning

movements. We propose that these costs may be additive and that each may be “priced” in terms of utility for the movement planner. However, in most movements there will be utilities that are a function of the movement outcome itself. A reach for a wine glass that succeeds and leads to a more rapid drink may be pleasant, but the consequences of failure (wine spilled on the new carpet or a broken glass owing to a collision along the way) may offset any desire to speed up the reach. Thus, we seek a way to frame the tradeoff between a small probability of a collision with an obstacle and a large decrease in the chances of achieving the goal of the task. Why might a subject be more willing to risk collision with an obstacle as the reward associated with successful completion of the task is increased?

There is considerable evidence that the motor system takes its own uncertainty into account when planning movements. Consider the task of moving the hand quickly to a target. The task is more difficult for shorter movement times, and for smaller and more distant targets. Subjects consistently prolonged their movement time for smaller target diameters (Fitts, 1954). Under natural reaching conditions, subjects take the uncertainty associated with their movement into account and select movement times that allow the target to be hit with constant reliability (Meyer *et al.*, 1988).

In our own work on movement-planning under risk, we make the connection between movement outcome and its consequences explicit. In our movement tasks, subjects receive monetary rewards based on the



**FIGURE 8.3** A movement task equivalent to decision making under risk. Subjects were required to touch a computer screen within a short period of time (e.g. 700ms). Subjects won 100 points by hitting inside the green circle and lost 500 points by hitting the background, as long as the movement was completed before the time limit, but a large penalty (700 points) was imposed for movements that were too slow. Because movements were rapid, they were also variable: the finger did not always land where the subject intended. As a result, it was in the best interest of the subject to aim to the right of the center of the green circle, compromising between the loss of points due to occasionally missing the green target circle and the loss of points due to occasionally landing in the red penalty circle.

outcome of their hand movement. The central difficulty for the movement planner in these tasks is that, with speeded movement, planned movement will differ from actual movement due to motor noise. As a result, the exact outcome of the hand movement is stochastic and the choice of a movement plan simply serves to assign probabilities to each movement outcome.

In our studies, subjects pointed rapidly at stimulus configurations consisting of a small target and nearby penalty region (Figure 8.3). Hand movements that ended within the green target circle yielded a small monetary reward; those ending in the red penalty circle could result in a loss. Endpoints in the target-penalty overlap region led to the awarding of both the reward and the penalty. A time limit was imposed, and movements that arrived after the time limit resulted in large penalties. Target size and the distance between target and penalty regions were small (<2cm), similar in size to the subject's movement endpoint variability. The movement plan that maximizes expected gain under these conditions depends on the relative position of the target and penalty circle, on the loss assigned to the penalty region, and on the subject's endpoint variability; this is explained next.

How should a subject perform this task? Clearly, the subject's visuo-motor strategy should take into account motor uncertainty and the penalty structure

imposed by the task. Our model of optimal performance is built on the following assumptions:

1. When the motor system selects a visuo-motor strategy, it in effect imposes a probability density on the space of possible movement trajectories that could occur once the motor strategy is executed. This probability density is likely affected by the goal of the movement, the planned duration, the possibility of visual feedback during the movement, previous training, and intrinsic uncertainty in the motor system (see, for example, Tassinari *et al.*, 2006; Dean *et al.*, 2007). We emphasize that the consequences for the subject are completely mediated through this probability density, and we can, for the most part, ignore the details of the actual mechanisms that produce and steer the action.
2. Whatever the penalty structure of the task, the penalty incurred by the subject depends only on the motion trajectory that *actually* occurs.
3. The subject acts so as to produce maximum expected gain (MEG) as computed from the magnitude of each possible reward and penalty and the probability of incurring it.

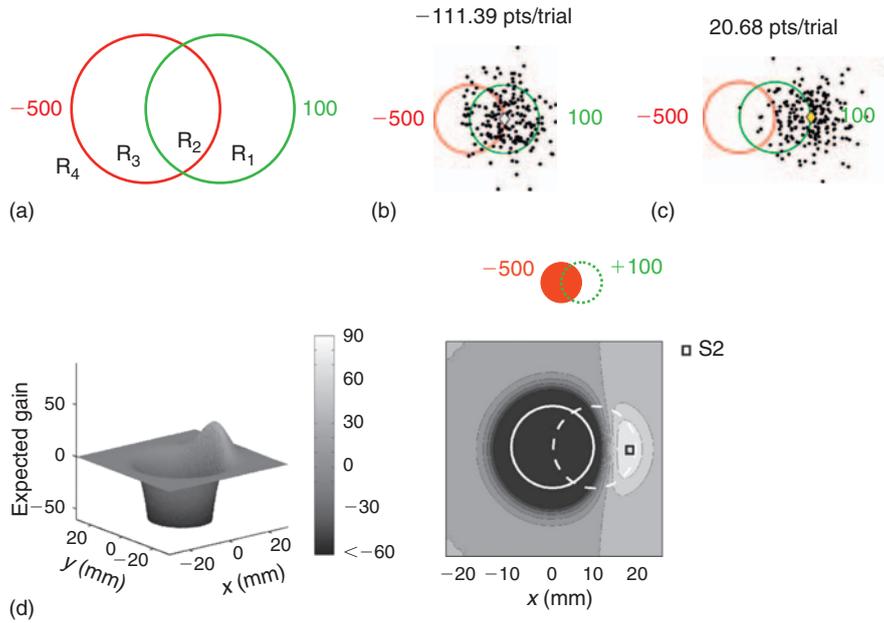
According to this model, the goal of movement planning is to select an optimal visuo-motor movement strategy (i.e. a movement plan) that specifies a desired movement trajectory. In this model, the optimal movement strategy is the one that maximizes expected gain. The model takes into account explicit gains associated with the possible outcomes of the movement, the mover's own task-relevant variability, and costs associated with the time limits imposed on the mover.

For the conditions of this experiment, the scene is divided into four regions (Figure 8.4a): the reward-only region  $R_1$  with gain  $G_1$ ,<sup>1</sup> the overlap region  $R_2$  with gain  $G_2$ , the penalty-only region  $R_3$  with gain  $G_3$ , and the background region  $R_4$  with gain  $G_4 = 0$ . We define an optimal visuo-motor strategy  $S$  as one that maximizes the subject's expected gain

$$\Gamma(S) = \sum_{i=1}^4 G_i P(R_i | S) + G_{\text{timeout}} P(\text{timeout} | S). \quad (8.1)$$

Here,  $P(R_i | S)$  is the probability, given a particular choice of strategy  $S$ , of reaching region  $R_i$  before the time limit ( $t = \text{timeout}$ ) has expired,

<sup>1</sup>Here we refer to outcomes as gains denoted  $G_i$  with losses coded as negative gains. The term "expected gain" that we use corresponds exactly to expected value in the psychological and economic literature.



**FIGURE 8.4** Equivalence between movement under risk and decision making under risk. (a) There are four regions in which the endpoint can land in the task outlined in Figure 8.3: reward-only (region with expected gain +100), reward–penalty overlap (region with expected gain –400), penalty-only (region with expected gain –500) and background (region with expected gain 0). (b) Sample endpoints for a subject aiming at the center of the green target (aim point indicated by the white diamond). This subject had a motor uncertainty of 5.6 mm (standard deviation); target and penalty circles have radii of 9 mm. The combination of motor uncertainty and aim point specifies the probability of landing in each region. This movement strategy yields an expected gain of –111.39 points/trial due to the high frequency of touching inside the red penalty circle. (c) Sample endpoints for the same subject aiming to the right of the target center to avoid accidental hits inside the penalty circle. The expected gain = 20.68 points/trial corresponds to the optimal strategy maximizing expected gain. (d) Expected gain for this subject as a function of mean movement endpoint. The maximum of this function corresponds to the aim point illustrated in (c).

$$P(R_i|S) = \int_{R_i^{\text{timeout}}} P(\tau|S)d\tau, \quad (8.2)$$

where  $R_i^{\text{timeout}}$  is the set of trajectories  $\tau$  that pass through  $R_i$  at some time after the start of the execution of the visuo-motor strategy and before the timeout. The task involves a penalty for not responding before the time limit ( $G_{\text{timeout}}$ ). The probability that a visuo-motor strategy  $S$  leads to a timeout is  $P(\text{timeout}|S)$ .

In our experiments, subjects win or lose points by touching the reward and penalty regions on the plane of the display before the timeout. Penalties and rewards depend only on the position of the endpoint in this plane, so a strategy  $S$  can be identified with the mean endpoint on the plane  $(\bar{x}, \bar{y})$  that results from adopting a particular choice of strategy  $S$  that results in that mean endpoint.

In most of our experiments, subjects' movement variance was the same in the vertical and horizontal directions, indistinguishable from a bivariate Gaussian distribution (see Figure 8.4b, 8.4c for simulated data for two aim points), and remained stable throughout

the experiment (see, for example, Trommershäuser *et al.*, 2003a, 2005; Wu *et al.*, 2006). Thus, we assume that the movement endpoints  $(x, y)$  are distributed according to a spatially isotropic Gaussian distribution with standard deviation  $\sigma$ ,

$$p(x, y|\bar{x}, \bar{y}, \sigma^2) = \frac{1}{2\pi\sigma^2} \exp(-((x - \bar{x})^2 + (y - \bar{y})^2)/2\sigma^2). \quad (8.3)$$

The probability of hitting region  $R_i$  is then

$$P(R_i|\bar{x}, \bar{y}, \sigma^2) = \int_{R_i} p(x, y|\bar{x}, \bar{y}, \sigma^2) dx dy. \quad (8.4)$$

In our experiments, the probability of a timeout is effectively constant over the limited range of relevant screen locations so, for a given endpoint variance  $\sigma^2$ , finding an optimal movement strategy corresponds to choosing a strategy with mean aim point  $(\bar{x}, \bar{y})$  that maximizes

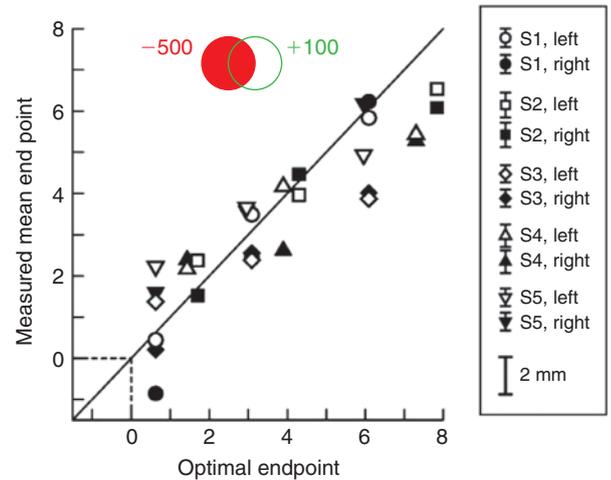
$$\Gamma(\bar{x}, \bar{y}) = \sum_{i=1}^4 G_i P(R_i | \bar{x}, \bar{y}, \sigma^2). \quad (8.5)$$

The maximum of  $\Gamma(\bar{x}, \bar{y})$  corresponds to the strategy maximizing expected gain, and depends on the position and magnitude of the penalty and on the distribution of the subject's endpoints (Figure 8.4d). When the penalty is zero, the aim point maximizing expected gain (and hence the mean endpoint maximizing expected gain) is the center of the target region. When the penalty is non-zero, the aim point maximizing expected gain shifts away from the penalty region and, therefore, away from the center of the target. This optimal shift is larger for greater penalties, for penalty regions closer to the target, and for larger magnitudes of motor variability.

For all conditions, we compared subjects' mean endpoints with those of a movement planner that maximized expected gain by taking into account its own task-relevant variability. Once we had measured the task-relevant variability for each subject and for each condition, our model yielded parameter-free predictions of behavior maximizing expected gain for all experimental conditions against which subject behavior could be compared.

The subjects in our experiments chose strategies maximizing expected gain (MEG), or nearly so (Figure 8.5). Efficiency was defined as the amount of money won relative to the amount of money expected for a subject who used the strategy maximizing expected gain. Subjects' efficiencies were typically above 90% (Trommershäuser *et al.*, 2003a, 2003b, 2005, 2006a; Dean *et al.*, 2007). Subjects chose visuo-motor strategies that came close to maximizing gain in a wide variety of simple stimulus configurations, in good agreement with the predictions for the subject maximizing expected gain (Trommershäuser *et al.*, 2003a, 2003b, 2005, 2006a, 2006b; Gepshtein *et al.*, 2007; Stritzke and Trommershäuser, 2007).

The experiments just described focused on spatial movement uncertainty and its consequences for behavior. Time played a role, but only in the time limit imposed on completion of movements to the target area. More recent experiments focus on compensation for temporal uncertainty and, more generally, the allocation of available time. Hudson *et al.* (2008) carried out experiments analogous to Trommershäuser *et al.* (2003a, 2003b), but with subjects rewarded for making touching movements that arrived at a target within a specified time window. If the subject missed the target or arrived outside of the time window, no reward was given. In different experimental conditions the subject could also be penalized for arriving early or late, as



**FIGURE 8.5** Movement strategies during rapid movement under risk. Measured mean movement endpoint as a function of optimal endpoint maximizing expected gain (data reprinted from Trommershäuser *et al.*, 2003b) in the task illustrated in Figure 8.3. Five subjects participated. There were six different conditions corresponding to green target circles located to the left (open symbols) or right (filled symbols) of the red penalty circle at each of three different target-penalty distances. The data points fall close to the diagonal identity line, indicating that subjects chose aim points close to those maximizing expected gain based on their individual movement variances.

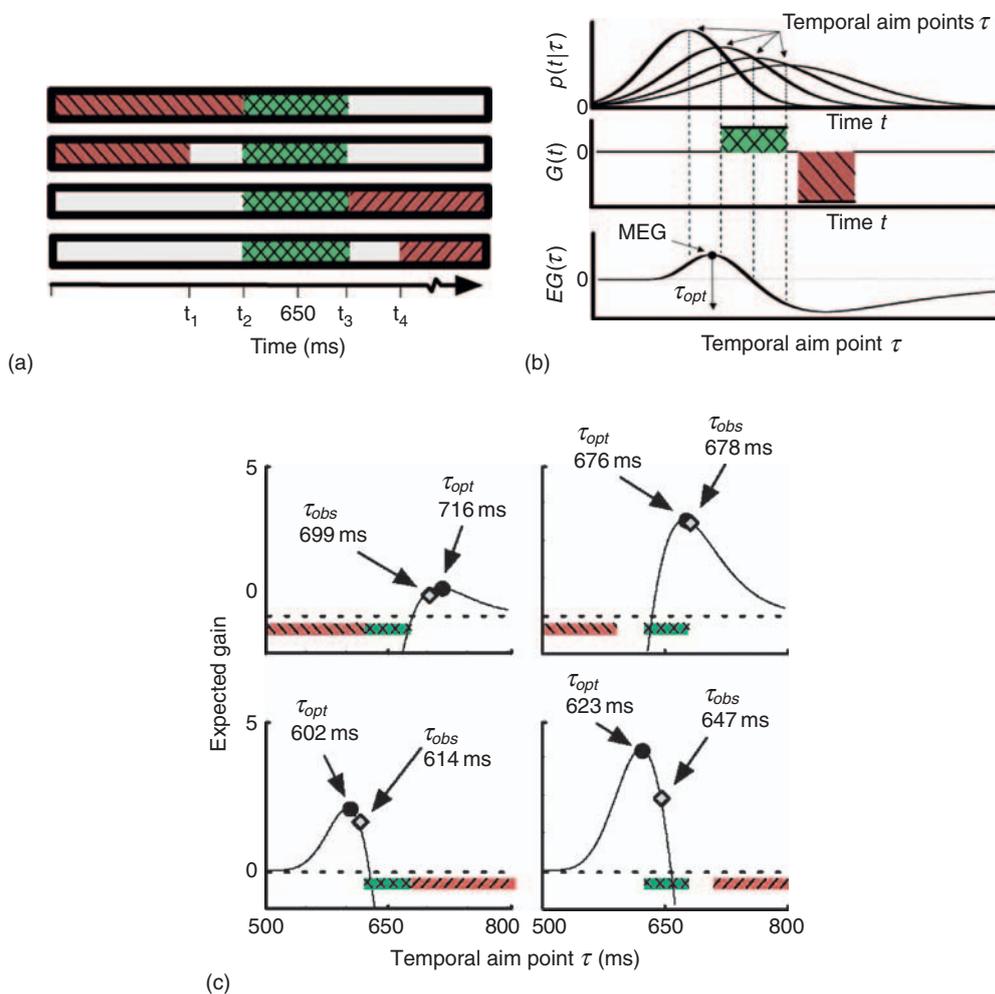
summarized in Figure 8.6a. Each of the bars is a time line, and the reward window is colored green. Arriving at times colored in red incurred a penalty, and arriving at times colored neither red nor green incurred no penalty and also no reward. The four reward/penalty conditions in Figure 8.6a were blocked and subjects were informed about the reward/penalty structure; they saw a display similar to the time bars in Figure 8.6a. The challenge for the subject was to compensate for the subject's own temporal movement uncertainty. Figure 8.6b illustrates the one-dimensional computation of expected gain as a function of the temporal aim point selected by the subject. The computation is analogous to that described by Trommershäuser *et al.* (2003a, 2003b), but is now computed in one temporal dimension rather than two spatial dimensions. One difference between the spatial experiments and the temporal experiment of Hudson and colleagues is that temporal movement uncertainty increases with duration of the movement. Hudson *et al.* found that subjects chose temporal aim points in good agreement with those predicted to maximize expected gain in each condition (Figure 8.6c). Moreover, each subject compensated for the increase in timing uncertainty with movements of longer duration.

Dean *et al.* (2007) studied how well subjects traded off speed and accuracy in attempting to hit targets whose value rapidly diminished over time. Once the

target appeared, its value decreased from an initial maximum to 0 over 700–1000ms, depending on condition. The subject received the value associated with the target at the instant that it was hit. If the subject missed the target, of course no reward was given. The challenge for the subject was to determine how to invest a scarce resource (time) by finding the compromise between increasing movement accuracy (by slowing down) and maximizing the value of the target when hit (by speeding up). Dean *et al.* measured subjects' performance in an initial training session, and used these data to estimate each subject's probability of hitting the target as a function of movement duration. This curve

is shown in Figure 8.7 (solid curve), together with a dashed line of negative slope that represents the rapidly decreasing value of the target. The product of these two curves is the expected gain as a function of movement duration, and the movement duration associated with maximum expected gain is marked with a circle. The experiment included four conditions that differed in how rapidly the value of the target decreased.

Dean *et al.* found that eight subjects increased or decreased movement duration from condition to condition in accord with predicted MEG duration, but that, overall, subjects were typically 50ms slow in arriving at the target. This delay was not costly

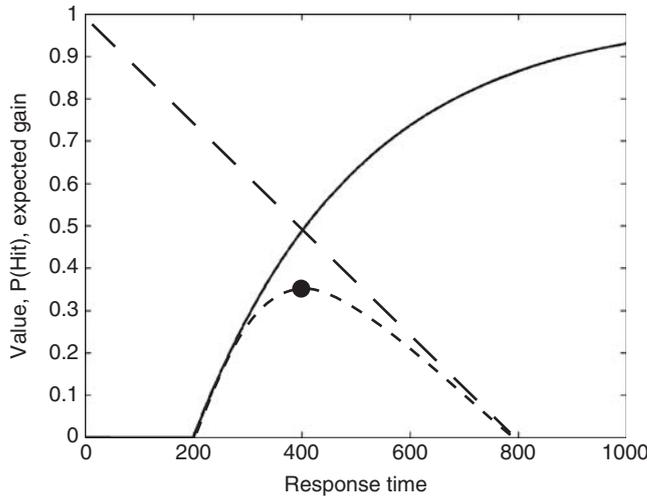


**FIGURE 8.6** Movement timing under risk. (a) In this task, subjects reached toward a target and were rewarded if they hit the target arriving within a fixed range of movement times (as indicated by the green portions of these timer bars). In four different conditions, either early or late movements arriving within a second range of movement times were penalized (the red portions of the timer bars). (b) Calculation of expected gain as a function of mean movement duration. Upper panel: distribution of movement times for several mean durations. Note that variance increases with mean duration. Middle panel: expected gain as a function of actual movement duration for one condition. Bottom panel: expected gain varies with mean movement duration; the black circle denotes the mean duration resulting in maximum expected gain. (c) Predictions for one subject; the four panels correspond to the four conditions in (a). Black circles indicate the MEG mean temporal aim point. Diamonds indicate observed mean durations. Across the four conditions and five subjects, mean movement durations were close to those that would result in maximum expected gain (Hudson *et al.*, 2008).

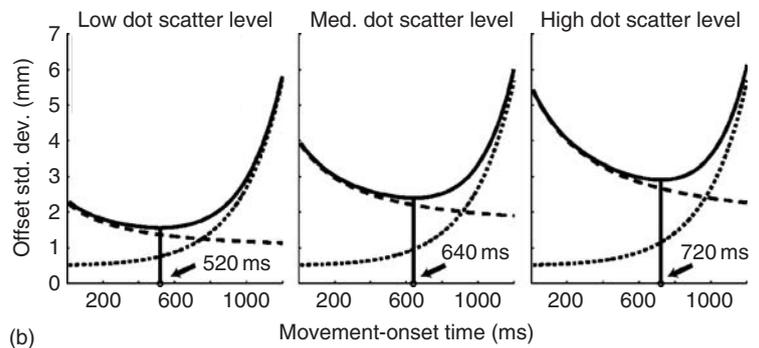
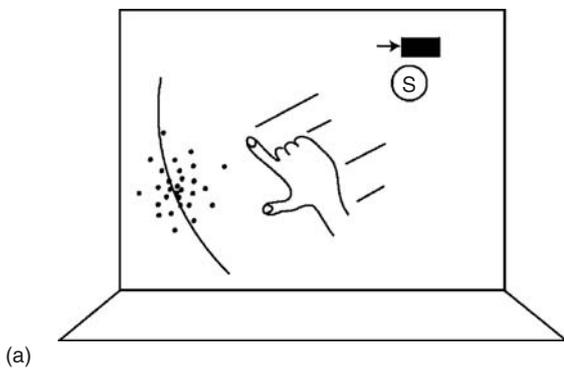
(almost all subjects earned 90% or more of their predicted MEG), but it was consistent across subjects and conditions. The authors conjectured that this 50ms delay might represent a tradeoff between monetary gain and biomechanical cost, as proposed by Trommershäuser *et al.* (2003a, 2003b). In effect, subjects sacrificed some of their potential winnings (about

\$0.001/trial) to be able to move slightly less rapidly – a tradeoff of 50 ms per “millidollar.”

Battaglia and Schrater (2007) examined human performance in a task where subjects needed time to accurately estimate the location of a target, and also needed time to move to and touch the target to earn rewards. The target was indicated by a random sample of points drawn from a probability density whose centroid was the center of the otherwise invisible target (Figure 8.8a). The points appeared one by one across time, and the longer the subject waited to move the more points would be seen and the more accurate the visual estimate of target location. However, increased viewing time came at the expense of a reduced time allocated to the movement. Moreover, as soon as the subject initiated movement, no further dots marking the target location would appear. There were three experimental conditions with three different probability densities differing in standard deviation (“dot scatter level”). In separate control conditions, they measured the variability of reaches constrained by visual or motor variability alone. Summing these individual variances, they could predict the tradeoff between viewing and movement time that minimized the standard deviation of the endpoint of movement relative to the center of the target (Figure 8.8b). This tradeoff changed with dot scatter level. Their “results suggest that ... the brain understands how visual and motor variability depend on time and selects viewing and movement durations to minimize consequent errors” (Battaglia and Schrater, 2007: 6989). These three temporal experiments, taken together, indicate that the



**FIGURE 8.7** Calculation of expected gain in the experiment of Dean *et al.* (2007). Subjects reached for a target on a display screen and were rewarded if they hit the target. The value of a hit on the target decreased linearly with movement duration (dashed line). Increased movement duration results in decreased movement endpoint variance, leading to an increased probability of a hit on the target (solid curve). The product of the value and probability of a hit equals expected value (dotted curve). The duration corresponding to maximum expected gain is indicated by the circle.



**FIGURE 8.8** Task and calculation of the optimal movement strategy in the experiment of Battaglia and Schrater (2007). (a) Targets were indicated by dots drawn from a Gaussian distribution centered on the unseen target. Dots were drawn one by one at a constant rate and no more dots were drawn once the subject began to reach, so that subjects had more information concerning target location the longer they waited to move. “S” indicates the starting point of the reach and the unseen target was located on the circular arc. The black bar indicates the amount of time that had elapsed throughout each trial. (b) Hits on the target were rewarded only if they occurred within 1200ms of the display of the first dot. The x-axis indicates the time of movement onset. Larger movement-onset times leave less time available for the movement, resulting in greater standard deviation of endpoint location due to motor variability (dotted curve) but smaller standard deviation due to error in visual estimation of target location (dashed curve). The overall standard deviation (relative to the target center) determines the probability of reward. The minimal standard deviation (corresponding to the strategy maximizing expected gain) is indicated. This varied with the standard deviation of the probability from which the dots were sampled (“dot scatter level”) as shown in the three panels.

visual system can solve optimization problems involving allocation of a fundamental scarce resource – time.

## MOVEMENT PLANNING AND DECISION MAKING

### The Importance of Arbitrary Loss Functions

All the models of motor performance discussed above assume that an ideal motor system will adapt to the constraints of a given task by optimizing some measure of cost or expected gain. The three different classes of models examined differ only in the cost to be minimized or the gain to be maximized: biomechanical costs, movement reliability, or economic expected gain. Theories applying optimal control theory to modeling motor behavior (Harris and Wolpert, 1998; Todorov, 2004) as well as applying Bayesian decision theory to modeling adaptive motor behavior (Körding and Wolpert, 2004a), depend crucially on the choice of a fixed and arbitrary loss function. Most implementations of these theories use the mean squared error as the loss function, such that doubling an error quadruples the cost. However, deviations from this assumption have been found for large motor errors, suggesting that the motor system works as a robust estimator by imposing smaller penalties for large errors relative to small than would be expected with a mean-squared-error loss function (Körding and Wolpert, 2004b).

Bayesian inference is currently the most promising candidate for modeling adaptation of the motor system to persistent changes in the movement planner's environment. A movement strategy is a mapping from sensory input<sup>2</sup>  $v$  to a movement plan  $s(v)$ .

The expected gain associated with the choice of strategy  $s(v)$  is given by

$$EG(s) = \iiint g(\tau, w) p_T(\tau | s(v)) p_V(v | w) p_W(w) dv d\tau dw, \quad (8.6)$$

where  $W$  is the random state of the world with prior distribution  $p_W(w)$ ,  $V$  is sensory information about the state of the world with likelihood distribution  $p_V(v | w)$ , and  $T$  is the stochastic movement trajectory resulting from the executed movement plan  $s(v)$  with distribution  $p_T(\tau | s(v))$ . The term  $g(\tau, w)$  specifies the gain resulting from an actual trajectory  $\tau$  in the actual state of the world  $w$ . This gain function can incorporate the

gain associated with movement outcome (i.e., whether the actual trajectory  $\tau$  accomplished the goal specified by world state  $w$ ), but it can also incorporate the cost of the trajectory itself (i.e., biomechanical costs). Note that gains need not be determined by  $w$  and  $\tau$ ;  $g(\tau, w)$  need only represent the *expected* gain under those conditions.

Bayesian decision theory makes use of Bayes' rule, which states that one should calculate the *likelihood* of the state of the world, i.e. the probability of the sensory input given the hypothesized state of the world,  $p_V(v | w)$ . The likelihood is integrated with the *prior*  $p_W(w)$ , which reflects the subject's belief about the particular state of the world before the sensory input is received. The prior may reflect how probable it is that objects in the world have a particular size or are oriented in a particular way. By multiplying the prior and the likelihood and normalizing (scaling so that the probabilities over all possible states sum to 1), we can estimate the probability of the state given the sensory input  $p(w | v)$ , termed the *posterior* of the state. This posterior could then become the new prior belief, and could be further updated based on later sensory input (see, for example, review by Bays and Wolpert, 2006).

Motor adaptation in agreement with Bayesian inference has recently been demonstrated in a study in which subjects made online corrections to a reaching movement based on momentary visual feedback of hand position (Körding and Wolpert, 2004a). Visual feedback, presented midway through the movement, was displaced laterally by a distance that varied randomly from trial to trial. The range of displacements experienced over the course of many trials formed a prior probability distribution. According to the Bayesian model, the prior distribution was combined with the feedback on a given trial to provide the best estimate of the position error. For movements in which very precise visual feedback was given, the prior distribution of displacements had little influence on the estimate of hand position. However, when the visual feedback was artificially blurred, the state estimate became increasingly biased towards the mean of the prior distribution, as predicted by a Bayesian model. In a later study, Tassinari *et al.* (2006) asked subjects to point at targets indicated by unreliable visual information, where targets were drawn from a prior distribution. Subjects had previously been trained on the prior distribution. Subjects displayed a similar shift from the position indicated by the visual information toward the mean of the prior distribution, although the variation of shift amounts across experimental conditions was smaller than of the predicted shifts that would maximize expected gain.

A similar result was found in a task in which subjects' movements were disturbed by force pulses of

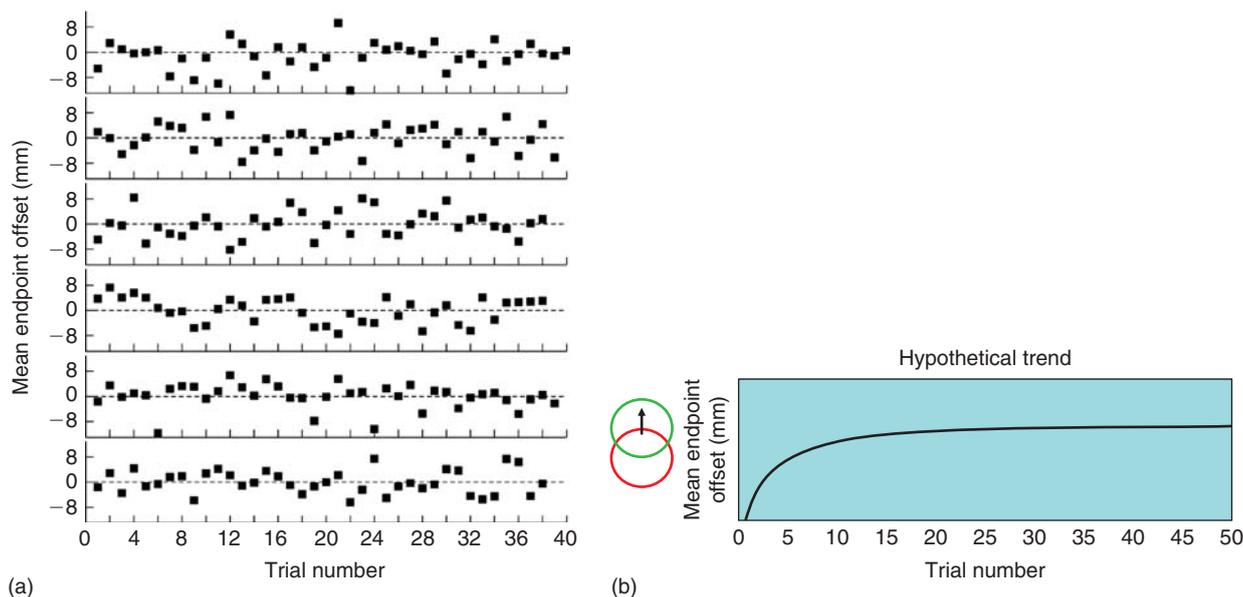
<sup>2</sup>We follow the convention that random variables are in upper case, e.g.  $X$ , while the corresponding specific values that those variables can take on are in lower case, e.g.  $p(x)$ .

varying amplitude (Körding *et al.*, 2004). The prior probability distribution of the strength of the force perturbation could be estimated by the subject as the distribution of forces experienced over the course of the experiment. Subjects experienced two force pulses during a single movement, and were told that they were of equal strength. Thus, to resist the second force pulse, subjects had to predict its strength by combining their estimate of the first pulse with their current estimate of the mean of the prior distribution. Subjects adapted their behavior in a manner consistent with the predictions of Bayesian integration of a noisy estimate of the force of the first pulse with the prior. The contribution of the prior depended appropriately on the prior information.

### Learning vs Computing

Surprisingly, subjects do not show a trend of gradually approaching maximum expected gain during these movement-planning tasks under risk. However, these effects may be explained by the specific design of the studies (e.g., Trommershäuser *et al.*, 2003a, 2003b, 2005; Dean *et al.*, 2007). Before the “decision-making” phase of the experiment, subjects practiced

the speeded motor task extensively by simply touching green targets. During this initial training period, the experimenter monitored their motor performance until subjects’ reaction times stabilized to the time constraints of the tasks and the experimenter could measure each subject’s residual motor variability. Following training, subjects learned about the gains and losses assigned to each region and were asked to try to earn as much money as they could by hitting the green circle and trying to avoid hitting the penalty region. Subjects were not explicitly instructed to work out a motor strategy that took into account the spatial locations of reward and penalty regions and the magnitude of penalty and reward, but their highly efficient performance indicates that they did so from the first trial in which rewards and penalties were specified. To summarize, in the design of Trommershäuser *et al.* (2003a, 2003b) and later work by Dean *et al.* (2007), subjects were first trained to be “motor experts” in speeded pointing towards single targets on the screen. Only then were they confronted with a task involving tradeoffs between possible rewards and penalties. As Trommershäuser *et al.* (2003a, 2003b, 2005) reported, there were no obvious trends in subjects’ aim points that would suggest that subjects were modifying their



**FIGURE 8.9** Consistency of pointing strategy across trials. (a) Trial-by-trial deviation of movement endpoint from mean movement endpoint as a function of trial number after introduction of rewards and penalties; the six different lines correspond to the six different spatial conditions of target and penalty offset (data replotted from Figure 7, Trommershäuser *et al.*, 2003a). (b) Trend of a hypothetical learning model in which a subject changes motor strategy gradually in response to rewards and penalties incurred. The subject initially aims at the center of the green circle. Before the subject’s first trial in the decision-making phase of the experiment, the subject is instructed that red circles carry penalties and green circles carry rewards. Subjects may approach the optimal aim point maximizing expected gain by slowly shifting the aim point away from the center of the green circle until the winnings match the maximum expected gain. However, the data shown in (a) do not exhibit this trend and do not support such a learning model.

decision-making strategy in response to their experience with the decision-making task (Figure 8.9a).

To see how unusual this finding is, consider applying a hypothetical learning model that changes motor strategy only gradually in response to rewards and penalties incurred (see, for example, Sutton and Barto, 1998; Dayan and Balleine, 2002; Daw and Doya, 2006). In the training part of our experiments, subjects learned to aim toward the center of the green circle. After the training, and before the subject's first trial in the decision-making phase of the experiment, the subject was instructed that red circles carry penalties and green circles carry rewards. What should the subject do on the first trial of the decision-making phase of the experiment? In the absence of any reward or penalty, a learning model based on reward and penalty would predict that the subject should aim at the center of the green circle, just as in the training trials. The subject would then gradually alter his/her motor strategy in response to the rewards and penalties incurred until the final motor strategy approximated the strategy maximizing expected gain (Figure 8.9b).

However, examination of the initial trials of the decision phase of the experiment (Figure 8.9a) suggests that subjects immediately changed their movement strategy from that used in training to that required to optimally trade off the probabilities of hitting the reward and penalty regions. This apparent lack of learning is of great interest in that it suggests that, while subjects certainly learned to carry out the motor task in the training phases of these experiments, and learned their own motor uncertainty, they seemed not to need further experience with the decision-making task to perform as well as they did.

## Motor and Perceptual Decisions

Comparing subjects' behavior with the predictions of an ideal performance model allows us to explore the limits of information processing during goal-directed behavior. In some of our previous work, we have varied basic parameters of the model asking how human behavior deviates from optimal behavior maximizing expected gain once the integration of sensory, motor, and reward information becomes too difficult or too time costly. Subjects do not always come close to maximizing expected gain in movement-planning tasks under risk. We find that subjects are able to optimally plan their movements, as long as full information about the stimulus configuration and the assigned rewards is provided prior to movement onset (Trommershäuser *et al.*, 2006b). Subjects fail to select strategies that maximize expected gain in motor

tasks similar to that of Trommershäuser *et al.* (2003a, 2003b) when there is a reward region and more than one penalty region (Wu *et al.*, 2006), when target and penalty circles are reduced in contrast and blurred (Ma-Wyatt *et al.*, 2006), and when rewards and penalties are awarded according to a stochastic payoff rule (Maloney *et al.*, 2007). Moreover, in unspedded *visual* tasks analogous to those of Trommershäuser *et al.* (2003a, 2003b), subjects fail to compensate for trial-to-trial variation in uncertainty (Landy *et al.*, 2007). Thus, while there is a collection of speeded motor tasks under risk where performance is remarkably efficient, we cannot simply generalize these results to a broader claim that performance in any perceptual or motor task under risk would be "near-optimal."

## Movement Under Risk, Decision Making Under Risk

In planning movement in our movement tasks under risk, our subjects are effectively choosing from among a set of many possible lotteries. To see why, consider a trial in which hits on the target and penalty yield gains of +1 and -5 cents, respectively (Figure 8.4a). In executing the movement, the subject chooses a strategy  $S$  which we've identified with the mean endpoint  $(\bar{x}, \bar{y})$ . The choice of strategy fixes the probability  $P(R_i | S)$  of hitting the target region, the penalty region, the region where target and penalty overlap, and the background, and hence of being awarded the gains  $G_i$  associated with each region. In the decision-making literature, this combination of event probabilities  $P(R_i | S)$  and associated gains  $G_i$  is called a "lottery"  $L(S)$ ,

$$L(S) = (P(R_1, S), G_1; P(R_2, S), G_2; P(R_3, S), G_3; P(R_4, S), G_4). \quad (8.7)$$

An alternative movement strategy  $S'$  corresponds to a second lottery

$$L(S') = (P(R_1, S'), G_1; P(R_2, S'), G_2; P(R_3, S'), G_3; P(R_4, S'), G_4). \quad (8.8)$$

As illustrated in Figure 8.4b-c, every mean endpoint results in a lottery with a corresponding expected gain, i.e., the expected number of points a subject will earn, on average, having "aimed" at  $(\bar{x}, \bar{y})$ . However, there are many other possible mean endpoints and corresponding lotteries, each with its associated expected gain. By choosing among all these possible strategies, the subjects in our experiments effectively select among the many possible lotteries.

The results of our experiments indicate that subjects choose strategies maximizing expected gain, or nearly so. Efficiency was defined as the amount of money won relative to the amount expected using an optimal strategy maximizing expected gain. Subjects' efficiencies were typically above 90% (Trommershäuser *et al.*, 2003a, 2003b).

In contrast to the highly efficient visuo-motor strategies observed during visuo-motor tasks under risk, human decision makers in decision making under risk typically fail to maximize expected gain. Expected utility theory (Bernoulli, 1738/1954; von Neumann and Morgenstern, 1944) is based on the assumption that subjects assign numerical utilities to outcomes and maximize expected utility. An evident advantage of the utility hypothesis is that a wide range of consequences (e.g., biomechanical costs and money) can be measured in identical units and it becomes meaningful to seek optimal tradeoffs among them. The model we presented assumes that this is the case.

When outcomes are specified as monetary rewards (as in our experiments), utility can be a non-linear function of monetary rewards and can also depend on subjects' current "wealth," and consequently a subject maximizing expected utility would fail to maximize expected gain. Bernoulli (1738/1954) originally suggested that this utility function is a concave function of value which increases quickly and then flattens out for larger values, and that the shape of the utility function could explain observed risk aversion in human decision making. Non-linear utility functions applied to gains and losses have been employed in describing human performance in a variety of economic decision tasks (Kahneman *et al.*, 1982; Bell *et al.*, 1988; Kahneman and Tversky, 2000). There is nothing inherently suboptimal or erroneous in maximizing expected utility, however it is defined, since by definition utility is what the organism seeks to maximize.

Moreover, several factors may have contributed to subjects' tendency to maximize expected gain found in our studies (Trommershäuser *et al.*, 2003a, 2003b, 2005; Dean *et al.*, 2007). In the motor task the subject makes a long series of choices and, over the course of the experiment, the accumulated winnings increase. On the other hand, subjects in economic decision making experiments typically make a single, "one-shot" choice between a discrete set of lotteries. Indeed, when economic decision makers are faced with a series of decisions, they tend to move closer to maximum expected gain (Redelmeier and Tversky, 1992; Wakker *et al.*, 1997; "the house money effect," Thaler and Johnson, 1990). Studies of risky choice find that subjects are closer to maximizing expected gain for small stakes (Camerer, 1992; Holt and Laury, 2002),

and when subjects receive feedback over the course of the experiment or have prior experience with the task (Hertwig *et al.*, 2004). All of these factors would tend to "linearize" subjects' utility functions and to move them toward maximizing expected gain.

However, human performance in decision-making tasks is markedly suboptimal by other relevant criteria. Deviations from expected utility theory include a tendency to change one's decision based on whether the lottery was described in terms of losses or gains, due to an exaggerated aversion to losses (Kahneman and Tversky, 1979) and a tendency to exaggerate small probabilities (Allais, 1953; Attneave, 1953; Lichtenstein *et al.*, 1978; Tversky and Kahneman, 1992). This exaggeration of the frequency of low-frequency events is observed in many, but not all, decision-making studies (Sedlmeier *et al.*, 1998). These distortions of probability would, if present in movement planning, be particularly problematic. The strategies maximizing expected gain in many of the motor tasks above involve small probabilities of large losses (Figure 8.4) and exaggerated-aversion of losses and overweighting of small probabilities would likely impair performance.

The contrast between success in "movement-planning under risk" and decision making under risk is heightened by the realization that, in cognitive decision making under risk, subjects are told the exact probabilities of outcomes and thus have perfect knowledge of how their choice of strategy changes the probability of attaining each outcome. The knowledge of probabilities in equivalent motor tasks is never communicated explicitly, but is acquired across a few hundred training trials, and thus can equal but never exceed the knowledge available under cognitive decision making under risk. The results of our experiments imply that subjects are able to learn their own motor uncertainties very well (Trommershäuser *et al.*, 2005; Gepshtein *et al.*, 2007; see also Baddeley *et al.*, 2003). These results suggest that humans are able to estimate the uncertainties associated with sensory and motor noise and make use of this knowledge to improve their performance.

In summary, the results of our work indicate that movement planning shares the same formal structure as perceptual decision making and economic decision making. Subjects in movement tasks are generally found to be very good at choosing motor strategies that come close to maximizing expected gain. In contrast, subjects in economic decision making and perceptual estimation tasks typically fail to maximize expected gain. Moreover, the sources of uncertainty in motor tasks are endogenous: they reflect the organism's own uncertainty in planning and executing movement while, in contrast, uncertainty in economic

tasks is typically imposed by the experimenter. Thus probabilistic information from cognition, perception, and movement has different origins, and it would be of interest for future work to compare the neural circuits underlying the representation of probability in movement and economic decision making.

## NEURAL CORRELATES OF MOTOR AND COGNITIVE DECISIONS

We finally summarize recent experimental work directed at understanding the neural coding of motor and cognitive decisions. Most of the current evidence results from electrophysiological recordings in monkeys measuring single-cell activity during binary-decision tasks in response to manipulations of reward and reward uncertainty (see, for example, Sugrue *et al.* (2005) for a review).

Following Herrnstein's (1961) pioneering behavioral work, electrophysiological studies typically employ a paradigm in which a monkey chooses between two alternative responses that may differ with respect to the sensory information available on each trial, the prior odds, and the outcome assigned to each response alternative. These experiments yield insight into how sensory information is integrated with reward information accumulated across previous trials. Reward is typically manipulated by assigning variable amounts of juice to different color-coded response alternatives (Platt and Glimcher, 1999; Sugrue *et al.*, 2004; see also Chapters 6, 30, and 32). When rewards were assigned stochastically, the monkey's choices appeared to be based on an estimate of the probability of reward gained by sampling over the last few trials (Sugrue *et al.*, 2004). These results indicate that the brain quickly reaches a decision based on the reward history of the last few trials.

Single cell activity in response to stochastic variations of reward has been found in ventral midbrain areas (Fiorillo *et al.*, 2003). These dopamine neurons' phasic activity correlates with the so-called prediction error, i.e. with the difference between actual and expected reward (Schultz *et al.*, 1997; Morris *et al.*, 2004; see also Part 4 of this volume, pp. 321–416), and modulating that activity affected choice (Pessiglione *et al.*, 2006). However, these same neurons also produced a tonic response that was highest in conditions of highest risk, i.e. in trials in which the probability of receiving the reward was 0.5. The behavioral relevance of this midbrain dopaminergic single cell activity recorded in response to changes in reward probability remains controversial (Bayer and Glimcher, 2005; Morris *et al.*, 2004; Niv *et al.*, 2006).

Using fMRI techniques in humans, a variety of subcortical and cortical areas have been implicated in the coding of decision variables such as expected gain, probability of reward, risk, and ambiguity. Most studies employ a visual representation of a gambling task and, after a delay of several seconds, subjects are instructed to choose between pairs of options by key-press. Brain activity is monitored during the delay period and correlated with various decision variables (see, for example, Glimcher and Rustichini, 2004; O'Doherty, 2004; Rorie and Newsome, 2005; Trepel *et al.*, 2005; Daw and Doya, 2006; Montague *et al.*, 2006). Neural activity may be correlated with gain or loss of a potential reward, the probability of reward, their product (expected gain) or risk (the variance of gain). A number of studies suggest that reward value is encoded in the striatum and portions of prefrontal cortex (PFC) and orbitofrontal cortex (OFC) (O'Doherty, 2004; Knutson *et al.*, 2005; Tanaka *et al.*, 2005; Daw *et al.*, 2006; Tom *et al.*, 2007).

In humans, reward-prediction error signals are generally found to be localized to the striatum, although they are also seen in OFC and amygdala (O'Doherty, 2004; Daw *et al.*, 2006; Pessiglione *et al.*, 2006; Yacubian *et al.*, 2006). It has been difficult to disentangle probability of reward from expected gain, and most studies find responses correlated with expected gain in the striatum, OFC and medial PFC (Delgado *et al.*, 2005; Hsu *et al.*, 2005; Knutson *et al.*, 2005; Daw *et al.*, 2006; Preuschoff *et al.*, 2006). Several of these studies see an increase in activity with increasing expected value whether or not the outcome is an expected loss or gain. On the other hand, Yacubian *et al.* (2006) suggest that while expected gains are encoded in the striatum, expected losses result in responses in the amygdala, perhaps also associated with negative emotion. This is supported by the finding that decisions consistent with framing effects are correlated with increased response in the amygdala. PFC response is higher in subjects that have less of a framing effect (De Martino *et al.*, 2006), suggesting a requirement for cognitive control to suppress this cognitive bias.

An important distinction in these gambling tasks is between risk (in which the probabilities of the outcomes are known precisely) and ambiguity (when they are not). Responses correlated with risk have been found in anterior insula, OFC and striatum (Preuschoff *et al.*, 2006), in the ventral striatum and anterior insula (Kuhnen and Knutson, 2005), as well as in dorsolateral PFC and posterior parietal cortex (Huettel *et al.*, 2005).

Responses correlated with the ambiguity of a decision have been found in the posterior part of the inferior frontal sulcus (Huettel *et al.*, 2006), OFC,

amygdala, and dorsomedial PFC, along with a negative correlation with responses in the striatum (Hsu *et al.*, 2005). Subjects with a preference for ambiguity over risk show stronger responses in lateral PFC, while subjects with a preference for risk over ambiguity show stronger responses in posterior parietal cortex (Huettel *et al.*, 2006). A reward received immediately is generally valued more than one that will be delayed – a phenomenon known as temporal discounting. If a reward will be received immediately, a variety of brain areas respond, including striatum and OFC; however, the inclusion of a potentially delayed reward recruits other areas, including portions of the PFC (McClure *et al.*, 2004; Tanaka *et al.*, 2005; Glimcher *et al.*, 2007), suggesting the need for cognitive control for choices involving delayed gratification.

Little is known about the neural coding of errors in pure motor tasks. Comparing errors in movement completion (induced by target displacements) with kinematic errors (induced by novel visual feedback) and with dynamic errors (induced by the application of force fields) showed increased cerebellar activity both for kinematic and for dynamic errors (Diedrichsen *et al.*, 2005). Target errors, but not execution errors, activated the posterior superior parietal lobule and the striatum. In contrast, execution errors produced strong adaptive responses that specifically activated anterior aspects of the parietal cortex and the dorsal premotor cortex. Overall, structures involved in the correction of errors attributable to mis-estimation of dynamics were generally a subset of the neural areas involved in correction of movement errors attributable to mis-estimation of kinematics.

## CONCLUSION

We have presented results from a variety of different approaches directed at understanding the processes underlying decision making in motor tasks. The results presented here indicate that movement planning shares the same formal structure as economic decision making. Subjects in movement tasks are generally found to be very good at choosing motor strategies that come close to maximizing expected gain. In contrast, subjects in economic decision making typically fail to maximize expected gain. Moreover, the sources of uncertainty in motor tasks are endogenous; they reflect the organism's own uncertainty in planning movement while, in contrast, uncertainty in economic tasks is typically imposed by the experimenter. Thus, probabilistic information from cognition, perception, and movement has different origins.

In economic decision tasks, feedback regarding outcomes typically reduces biases and misperceptions in the representation of probability estimates, moving behavior closer to strategies maximizing expected gain. We emphasize that in movement-planning under risk subjects' performance is initially close to optimal performance, maximizing expected gain, and does not appear to change with feedback. Movement planning is well described by simple models that maximize expected gain while there is no single model of economic decision making that captures all of the complexity of human behavior. Careful study of the neural circuitry underlying decision making in the form of movement could lead to a better understanding of how the brain gathers information to make decisions and transforms them into movement.

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