

# EXTENSION PACK FOR ALFA PLATFORM

2025.1



Hardware requirements	
What is needed?	
Therapeutic tasks database	5
Speed	5
Movement precision	9
Functional movements	11
Problem solving	29

# WHAT IS NEEDED?

Please make sure the PC where you want this module to be active have VAST.Rehab Patient Panel installed and that the following hardware requirements are met:

- Windows 10/11
- Intel Core i5 (8th gen or newer). Important: Avoid ultra-low-power versions (e.g., i5-8250U), as they may not meet performance requirements. Prefer standard or high-performance CPUs.
- Minimum: 8 GB RAM (16 GB or more recommended for optimal performance).





# SPEED RABBIT

Measure number of repetitions of specific movement pattern an individual is able to perform within predefined time interval.

### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range

#### **OBJECTIVES**

- Speed of movement
- Repetitive movements

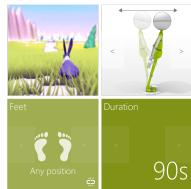
#### **INSTRUCTION FOR PATIENT**

Go through the entire route as fast as you can.











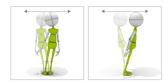




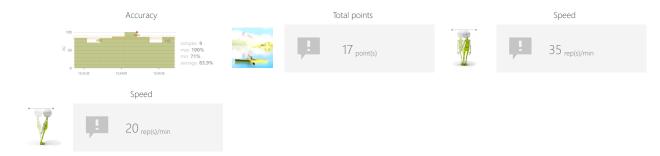
# SPEED KAYAK

Measure number of repetitions of specific movement pattern an individual is able to perform within predefined time interval.

# **CONTROL MODES**



# **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range

#### **OBJECTIVES**

- Speed of movement
- Repetitive movements

#### **INSTRUCTION FOR PATIENT**

Row as fast as you can.











# MOVEMENT PRECISION UMBRELLA

Measure and train individual's skills to perform specific movement patterns with predefined speed and range.

### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Path
- Range
- Umbrella size

#### **OBJECTIVES**

- Movement precision
- Visual motor coordination

#### **INSTRUCTION FOR PATIENT**

Don't let the hippo get wet - keep the umbrella above him!











#### **CANNON**

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range
- Time between cannonballs
- Time between enemies
- Enemies speed

#### **OBJECTIVES**

- Planning and Strategy
- Movement precision
- Predicting the trajectory of objects

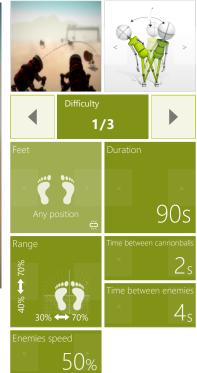
#### INSTRUCTION FOR PATIENT

Use the cannon(s) to shoot into the robots coming in your direction.















#### **AUTOMATIC CANNON**

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range
- Enable distractors
- Time between cannonballs
- Time between enemies
- Enemies speed

#### **OBJECTIVES**

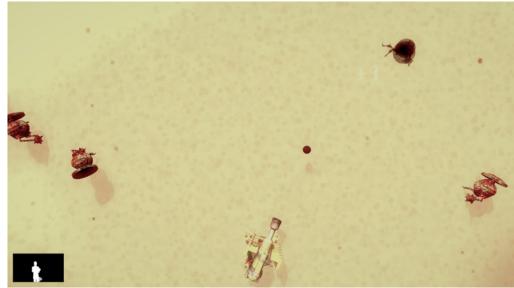
- Divided attention
- Spontaneous movements
- Predicting the trajectory of objects

#### INSTRUCTION FOR PATIENT

Control cannon(s) to destroy robots, but avoid hitting the elephant!















#### **DRAGON**

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range
- Coins group size
- Distance between coins
- Gravity force

#### **OBJECTIVES**

- Predicting the trajectory of objects
- Improve range of motion
- Visual motor coordination
- Muscle strengthening
- Planning and Strategy

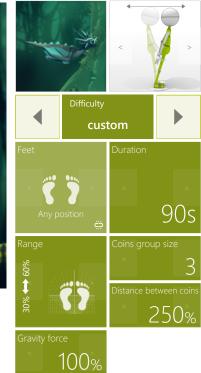
#### INSTRUCTION FOR PATIENT

Fly and collect the coins.















#### **ROCKET JUMPING**

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range
- Time between objects
- Bomb format
- Speed of objects

#### **OBJECTIVES**

- Spontaneous movements
- Dynamic responses to emerging moving targets
- Predicting the trajectory of objects

#### INSTRUCTION FOR PATIENT

Help the creature jump over incoming rockets and avoid being hit.











#### **RAILS**

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Speed
- Feet position
- Task duration
- Range
- Route shape
- Enable derailing
- Enable obstacles
- Time between objects

#### **OBJECTIVES**

- Dynamic responses to emerging moving targets
- Predicting the trajectory of objects
- Visual motor coordination

#### INSTRUCTION FOR PATIENT

Control the trolley to collect the coins.















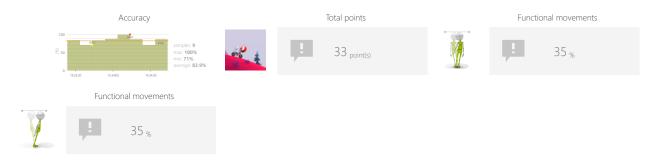
### **MOTOCROSS**

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range
- Route shape

#### **OBJECTIVES**

- Dynamics of planned movements
- Planning and Strategy

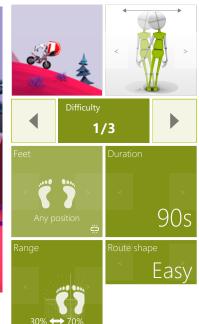
#### INSTRUCTION FOR PATIENT

Accelerate and brake to cover the entire route as quickly as possible without tipping.











#### **FOREST RUNNER**

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Speed
- Feet position
- Task duration
- Range

#### **OBJECTIVES**

- Dynamics of planned movements
- Focusing
- Planned movements
- Speed of movement

#### INSTRUCTION FOR PATIENT

Keep the hare on the run, avoid obstacles and collect as many carrots as you can.











#### **GEOMETRY FLIER**

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Speed
- Feet position
- Task duration
- Range

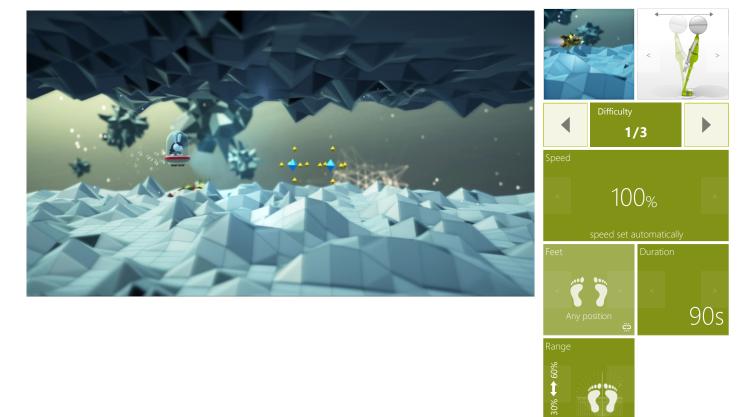
#### **OBJECTIVES**

- Dynamics of planned movements
- Activity in a given rhythm
- Visual motor coordination

#### INSTRUCTION FOR PATIENT

Control the vehicle to avoid the obstacles.







### DANCEMAN

Measure and train individual's skills to perform movements based on real-world situational biomechanics. They usually involve multi-planar, multi-joint movements which place demand on the body's core musculature and innervation.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range
- Advanced scoring
- Song index
- Spawn rate level

#### **OBJECTIVES**

- · Activity in a given rhythm
- Spontaneous movements
- Visual motor coordination

#### INSTRUCTION FOR PATIENT

Hit the green characters when they come close.









# PROBLEM SOLVING

#### **MAZE**

Measure and train individual's skills to reach a solution of specific problems. Problem solving may include mathematical or systematic operations and can be a gauge of an individual's critical thinking skills.

#### **CONTROL MODES**



#### **RESULTS**



#### **ADJUSTMENTS**

- Feet position
- Task duration
- Range
- Show path
- Maze size

#### **OBJECTIVES**

- Logical tasks
- Planned movements
- Planning and Strategy

#### INSTRUCTION FOR PATIENT

Lead the hippo through the maze to the glowing target.







