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### Abstract

#### Effects of the Foot Position on Standing Balance in Patients With Hemiplegia

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The purpose of this study was to investigate whether the standing balance could be influenced by the different foot positions. Seventeen patients with hemiplegia were tested for the static and dynamic balance under the different foot positions. In the balance test, subject stood by bearing weight on one foot, and the other foot was positioned in three different positions (symmetric, 45° anterolateral, and anterior position). This study used the Kinesthetic ability trainer (KAT2000) to measure the standing balance. The results were as follows: 1) There were significant differences in the static standing balance in different foot positions with both weight-bearing on the paretic limb and on the nonparetic limb ( $p < .05$ ). 2) There were also significant differences in the dynamic standing balance in different foot positions with both weight-bearing on the paretic limb and on the nonparetic limb ( $p < .05$ ). 3) There was a significant difference when the paretic weight-bearing and the nonparetic weight-bearing were compared ( $p < .01$ ). 4) when the paretic weight-bearing and the nonparetic weight-bearing were compared, anterior foot position showed a significant difference in the dynamic standing balance ( $p < .05$ ), but 45° anterolateral foot position did not show a significant difference ( $p > .05$ ). In this study, the standing balance showed a significant difference according to different foot positions in hemiparetic patients, and standing balance was better when they stood by bearing weight on the nonparetic limb. These results indicate that it is a necessary to consider both weight-bearing limb and foot position not only in the rehabilitation program but also in achieving the stability in the independent life.

**Key Words:** Static standing balance; Dynamic standing balance; Foot locations;  
Weight-bearing limb.

가 (King, 1994; Nevitt, 1991).  
(Wernick-Robinson, 1999).  
가 (Ek Dahl, 1989; Östlund, 1979),  
가 (Keenan, 1984).  
가 (Ek Dahl, 1989).  
Juntunen (1987)  
Era Heikkinen (1985), Ratliff (1987)  
Begbie (1969)  
(Berg, 1989; King, 1994).  
(Sackley, 1992),  
(Riley, 1990).  
가  
가 (, 2000).  
가 . Winstein (1989)  
(King, 1994). , Wollacott (1986)

. Keenan (1984) Kirby (1987) Lee (1988)  
가 , 가 , Murrary (1975)  
(Bohannon Leary, 1995). (1997) 가  
, Dettmann 가 가  
(1987) 가 가 가  
가 , 가 가  
가 60% 가 25%  
(Bobath, 1978; Winstein , 1989). 가  
가 가  
(Winstein 가  
, 1989). Dickstein (1984) 가  
가 1.  
가 , 1999; , 2000). 가  
2000 10 14  
11 9

17

.0 6.0

PSI 가 ,

2. 가

가

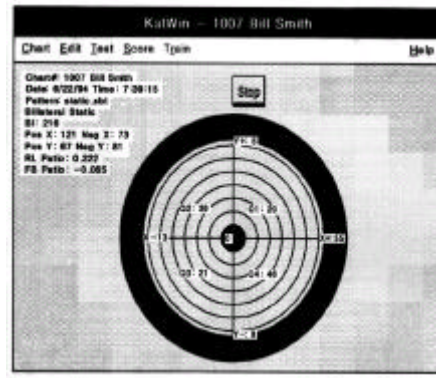
, 가  
 가 .

가

KAT2000<sup>1)</sup> ( 1).



1. Kinesthetic ability trainer (KAT2000)



2.

3.

KAT 2000

45°

( 3).

가

1°

3.5 mm

(balance index: BI)

( 2).

가

3.0 PSI

가

KAT 2000

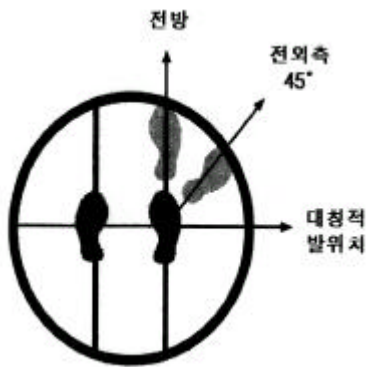
가

( 20 cm)

PSI (pounds per square inch)

1) Kinesthetic ability trainer. Berg. Inc., 1994.

가



3.

(handrail)  
 (training effect)  
 , 5 3  
 4.

SPSS/Window Version 7.5

(one-way repeated ANOVA)

, 20  
 (balance index: BI)

2).

가 가  
 가  
 가 45°  
 가

45°

( 3).

1.  
 11 , 6  
 17  
 57.8 , 64.7  
 60.2  
 165.3 cm, 155.0 cm ,  
 161.6 cm  
 63.9 kg, 52.2 kg  
 59.8 kg  
 26.1 cm, 24.1 cm  
 25.4 cm 가  
 12.2 , 가 9.2  
 11.1 ( 1).  
 10  
 (58.8%), 5 (29.4%), 1  
 (5.9%), 1 (5.9%)  
 1  
 17 3 (17.6%) ,

1. (n=17)

	( )	(cm)	(kg)	(cm)	( )
(11)	57.8 ± 15.9	165.3 ± 6.0	63.9 ± 9.6	26.1 ± 0.6	12.2 ± 8.6*
(6)	64.7 ± 10.2	155.0 ± 5.4	52.2 ± 7.8	24.1 ± 0.4	9.2 ± 8.8
(17)	60.2 ± 14.2	161.6 ± 7.6	59.8 ± 10.5	25.4 ± 1.1	11.1 ± 8.5

\* ±

2. (n=17)

	( )	(%)			
10	58.8	403.5,	336.0 ,		
5	29.4	45°	45°	649.1,	
1	5.9		612.0,		
1	5.9			1093.1	
3	17.6				
14	82.4		1924.7 ,		
9	52.9		45°		
8	47.1	2028.1,		2210.5,	
14 (82.4%)		45°			
가 9 (52.9%),			2285.6,		
가 8 (47.1%)				2686.3	
( 2).		( 3).			

3.

336.0 ± 334.9*		
	403.5 ± 495.2	649.1 ± 677.0
	612.0 ± 523.3	1093.1 ± 937.9
1924.7 ± 588.6		
	2028.1 ± 709.8	2210.5 ± 781.4
	2285.6 ± 849.7	2686.3 ± 954.4

\* ±

4. (n=17)

			F	p
9624932.1	16	601558.3	8.57	-
1065438.6	2	532719.3	7.59	.002
18525461.0	16	1157841.3	7.92	-
4921231.1	2	2460615.5	16.84	.000

5.

	p
	.741
	.002
	.016
	.058
	.000
	.005

3. 가 (p<.05),( 4).  
 가 Tukey  
 , 45° .  
 가 가  
 ,  
 45°  
 가 (p<.05),( 7).  
 가

6. (n=17)

			F	p
19563082.0	16	1222692.6	7.38	-
1226837.8	2	613418.9	3.70	.036
23532680.0	16	1470792.5	7.41	-
5032519.9	2	2516260.0	12.68	.000

7.

P	2028.1, 2210.5 (p>.05),	가
.766		
.034	2285.6,	
.147	2686.3	가 (p<.05),
.164	( 8).	
.000		
.011		

5.

45°

403.5,  
649.1,

612.0,  
1093.1  
가 (p<.01).

45°

가 , Horak(1987)

가 ,

가 ,

가 ,

8.

	±	t
	403.5 ± 495.2	- 3.57**
	649.1 ± 677.0	
	612.0 ± 523.3	- 3.78**
	1093.1 ± 937.9	
	2028.1 ± 709.8	- 1.48
	2010.5 ± 781.4	
	2285.6 ± 849.7	- 2.17*
	2686.3 ± 954.4	

\* p < .05, \*\* p < .01



(stability)  
가  
Dettmann (1987)  
가  
(Horak, 1987;  
Moore, 1986) Dickstein  
(center of gravity: COG) (1984)  
2  
cm (Horak, 1987;  
Murray, 1967). Murray (1975) Lee (1988)  
(center  
of mass)  
(functional base of support) (diagonal stance)  
Nichols(1997)  
가  
가  
가  
(, 2000; , 1995).  
Bobath(1978)  
가  
가  
Keenan (1984)  
가  
, Hamrin (1982) Dettmann  
(1987)  
가  
Keenan 가  
(1984) (Bohannon Leary, 1995).  
Eckert(1979)

45°

가 ( $p < .05$ ).

( $p < .05$ ).

Lee (1988)

Eckert(1979)가 ( $p < .01$ ), 45° 가

45° 가 ( $p > .05$ ). Dickstein

가

45°

(2000) 가

가 ( $p > 0.05$ ).

가

(Mills DiGenio, 1983),

가

( $p < .05$ ).

( $p < .05$ ).

가

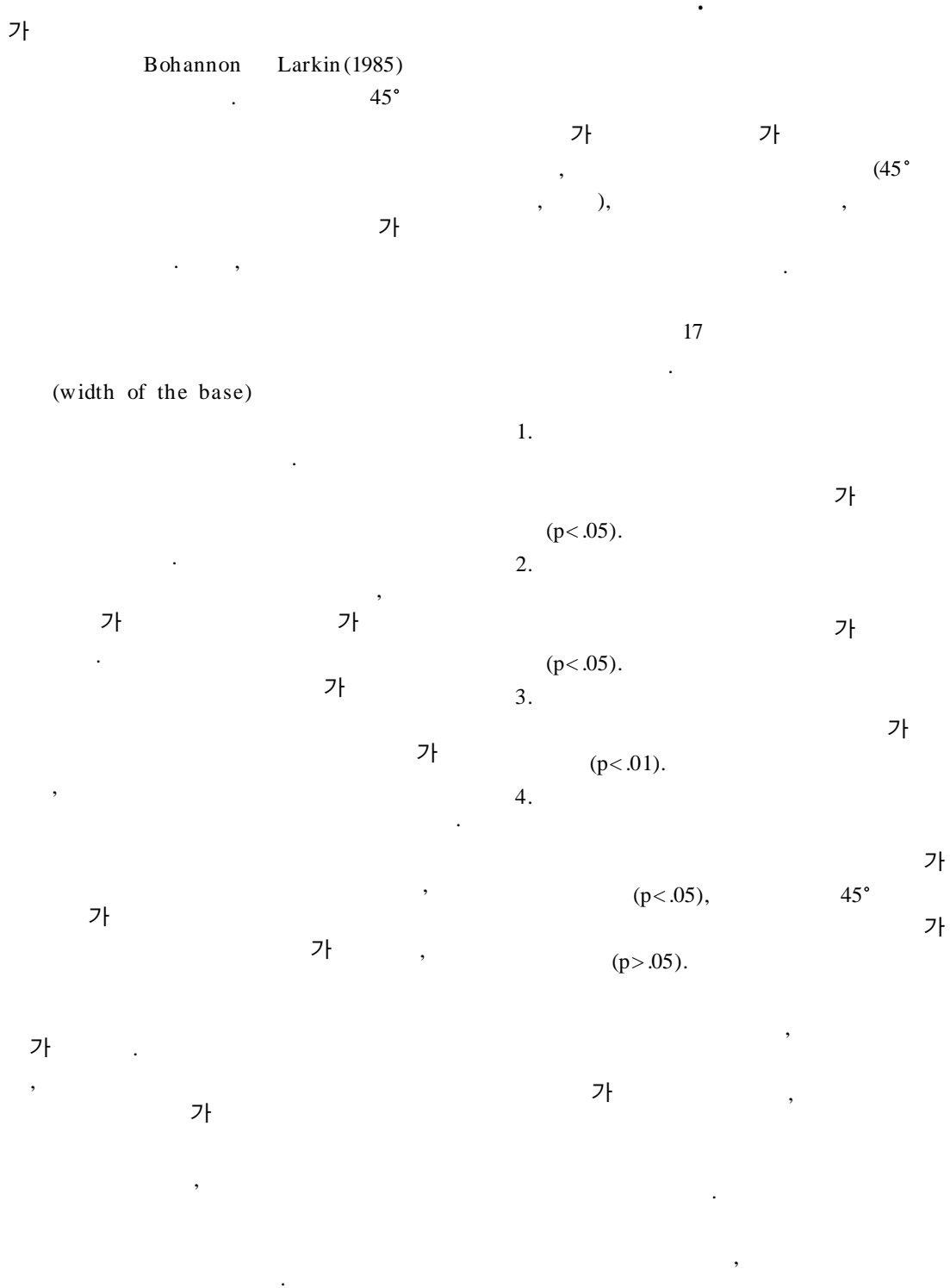
가

가

( $p < .05$ ).

45°

Nichols(1997)



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- 가  
7:1-18.
- 1995.
- 가  
1997;4:34-44.
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