

INDEX

- Accelerometers, 50–53
- Anthropometry, 11, 82–106
body, 82–100
experimental measures, 96–100
muscle, 100, 104
problems, 104, 105
tables, 86, 92, 94, 101
- Balance board, 97
- Biomechanical:
analyses, 5, 6
assessments, 2, 3, 6, 7
measurements, 2, 3, 48–63
models –inverted pendulum, 127–131,
289–294
monitoring, 3, 4
motor synergies, 12, 23, 25, 124, 125,
281–294
gait initiation, 290–293
gait termination, 293, 294
load/unload mechanism, 286–290
support moment, 124, 125,
282–285
trunk balance in gait, 23, 25
- Body:
center of gravity, 85, 158
center of mass, 33–35, 88, 89, 92–96,
127–131, 163, 286–294
density, 83–85
energy, 160–162
height, 82, 83
moment of inertia, 89–91, 95–98,
108–110, 190–192
ponderal index, 84
somatotype, 84
- Cardan rotation sequences, 177–179
- Center of pressure, 33–35, 109,
118–121, 123, 127–131, 133, 134,
286–294
- Cocontraction, 25, 26, 151, 152,
288–290
- Degrees of freedom, 205, 206, 208,
209
- Efficiency:
mechanical, 150, 151
muscle, 150
negative, 150
positive, 150
work, 150
- Electromyogram:
biophysical basis, 251–257
common mode rejection, 257, 261,
263–265
crosstalk, 23, 265–268
filters, 260–262
frequency content, 256, 257, 260–268,
276, 277

- Electromyogram (*continued*)
 gain, 258
 input impedance, 258–260
 integrated, 269, 270, 272
 linear envelope, 5, 25, 269–272
 motor unit action potential, 251–257
 in muscle model, 244–247
 presence of hum, 23, 24, 264, 265
 recording amplifiers, 257–269
- Energy:
 absorption, 142–146, 153, 154,
 161–165, 168–170, 195, 197,
 198
 exchange, 151–160
 generation, 141–146, 150, 153, 154,
 161–164, 168–170, 195, 197,
 198
 kinetic, 156–160, 215
 law of conservation of, 140, 141, 158
 metabolic, 150, 151, 154, 155
 potential, 155–159, 215
 problems, 173, 174
 spring, 216
 storage, 155–159
 total body, 160–162
 transfer, 148, 149, 167–172
- Euler rotation sequences, equations, 179,
 189–191
- Finite differences, 77, 78, 193
 Foot pressure measurement, 121, 122
 Force platforms, 117–123
 Forces:
 bone-on-bone, 110–112, 131–136
 gravitational, 109–116, 127–129
 ground reaction, 7, 113, 117–123
 inertial, 112–116, 128–130, 189–194
 muscle, 109, 111, 131–136, 227–247
 reaction, 108–116, 133–135, 188–194
- Forward solution, 12, 200–222
 assumptions, 201
 examples, 217–221
 formulation, 203–217
 potential use, 201, 202
 review, 202, 203
- Free body diagram. *See* Inverse solution
- Glove transducer, 50, 51
 Goniometers, 48–50
- Heats of contraction, 154, 155,
 245
 Hill's equation, 238
- Imaging techniques, 53–64
 cinematography, 55–58
 lens optics, 54, 55
 optoelectric, 61–63
 television, 58–61
- Inefficiency, causes, 151–154
 Inverse solution, 6, 107–110, 112–116,
 189–196
- Kinematics, 10, 45–80, 98–100,
 176–188
 acceleration calculation, 66, 67, 78
 angles, 75–77
 axes of rotation, 98–100
 conventions, 45, 47
 direct measures, 48–53
 imaging techniques, 53–64
 problems, 79, 80
 three-dimensional, 176–188
 two-dimensional, 45–80
 variables, 46–48
 velocity calculation, 77, 78
- Kinesiology, 1
 Kinetics, 10, 11, 107–136,
 188–198
 problems, 136, 137, 191–194
- Lagrangian equations, 205–208
 Link-segment model, 107–113, 188–191
 assumptions, 108, 109
- Moments-of-force, 41, 42, 108–110,
 112–116, 123–127, 131–133,
 188–198, 282–285
 erroneous calculation technique, 126,
 127
 interpretation, 124, 125, 194–196,
 198, 282–285

- Motor unit, 224–230, 251, 255
 action potential, 226, 250–257
 fast twitch, 228, 229
 final common pathway, 8, 251
 motor end plate, 224, 251
 muscle twitch, 8, 227–230
 recruitment, 225–228, 256, 257
 size principle, 8, 226–228
 slow twitch, 228, 229
- Muscle:
 active state, 244
 concentric contraction, 236–238
 contractile element, 225, 231–233, 244–246
 cross-sectional area, 82, 100–102
 eccentric contraction, 238, 239
 fatigue, 276, 277
 fibers, 224
 force–length characteristics, 231–235, 239–241
 force–velocity characteristics, 236–242
 length, 82, 101, 102
 mass, 101
 modeling, 131–135, 234, 243–246
 moment-arm length, 102–104, 131–135
 origin and insertion, 82, 133, 134
 parallel elastic element, 232–234
 pennation, 100, 101
 sarcomere, 225
 series elastic element, 233–235
 stress, 102
 tension vs. EMG, 244–247, 271–275
 tremor, 277
- Newtonian equations, 110, 112–116, 123, 189–194
- Parallel-axis theorem, 90, 91, 95
- Power, mechanical, 139–149, 163–165, 167–172, 195, 197
 balance of, 167, 168, 170–172
 muscle, 139–146, 153, 154, 161, 162, 164, 167–172, 194, 195, 197, 198
- Quick release technique, 97, 98
- Recruitment, 225–228, 256, 257
- Segment:
 definitions, 86, 94
 density, 84, 85
 energy, 148, 149, 155–163, 215, 216
 lengths, 85–87, 90, 94, 96, 97, 108
 mass, 85–87, 90, 91, 94, 96, 97, 108
 mass center, 83, 85–94, 108–110, 112–116, 120, 121, 123, 156, 189, 190
 moment of inertia, 83, 85–92
 radius of gyration, 86, 89–91, 95
- Signal Processing, 9, 10, 14–44, 68–78, 195–198, 266–268, 283, 284, 288–290
 aliasing, 31, 32
 analog-to-digital conversion, 30, 31
 calculating velocities & accelerations, 66, 67, 77, 78
 correlation analyses, 14–26, 266–268, 288–290
 auto, 14, 16–20, 22–24
 cross, 14, 16, 17, 20–23, 25, 26, 266–268, 288–290
 covariance analysis, 283, 284
 deciding record length, 33–35
 ensemble averaging, 25, 41–43, 195–198, 283
 harmonic, Fourier analysis, 27–30, 35–37
 Pearson, 15, 16, 285
 sampling theorem, 31–33
 smoothing of data, 67–75
 analog & digital filtering, 35–38, 68–75
 curve fitting, 68, 74, 75
 harmonic reconstitution, 38, 39, 68, 74, 75
 white noise, Fourier analysis, 39, 40
- Size principle, 226–228
- Spatial reference systems:
 global (GRS), 176, 177, 180–187, 189, 190, 208

Spatial reference systems (*continued*)

- local, anatomical (LRS), 176, 177, 180–187
- marker axis system, 180–186
- three-dimensional, 212, 214
- two-dimensional, 210–212, 217–221

Synthesis. *See* Forward solution

Work:

- against gravity, 152, 153
- examples, 140, 147, 148, 156, 157, 159
- external, 141–143, 146–148, 167
- internal, 141–143, 145, 146, 162–166
- muscle, 140, 143–146, 161, 162, 164
- negative, 144–146, 161, 162
- positive, 143–146, 161, 162