

1. [3]
- (a) (biomechanics)
 - (b) (human-body dynamics) (kinematics)
(kinetics) 2
 - (c) (human-body dynamics) (rigid body)
(particle) (flexible body)

2. [4] (relative reference system)
(absolute reference system)

3. [3] Table A.2 Filtered Kinematic Data stance
50 frame coordinate
- (a) spatial reference system shank (leg) absolute angle
 - (b) spatial reference system thigh absolute angle
 - (c) leg thigh가 knee joint angle
(+/-)

4. [3] Table A.2 Filtered Kinematic Data swing
frame data
- (a) x , 5 frame toe x
 - (b) x , 5 frame toe x 가
 - (c) x , 5 frame toe x 가

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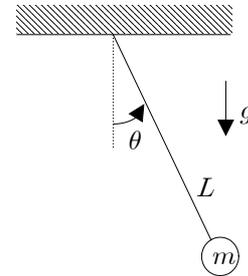
5. [4] ,
- (a) (thigh = knee hip) m ,
 (moment of inertia) I_0 .
- (b) (thigh)가 hip (moment of
 inertia) I_h .
6. [4] Given the kinematic data in Table A.3 and the knee reaction forces in Table A.5, calculate the reaction forces at the hip in the x and y directions for frame 20.
7. [4] Given the kinematic data in Table A.3 and the knee reaction forces and moments in Table A.5, calculate the hip moment of force for frame 90.

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1. [3] Figure 5.6 (elbow) , ,
 . (가 0 , t_1, t_2, \dots
 , t_5)

2. [4] Using segment angular velocity data in Table A.7 in the textbook plus appropriate data from other tables, calculate the power generation or absorption of the muscles at the ankle joint for frame 50.

3. [4] swing
 (pendulum)
 . Lagrange



4. [6] Table 7.3 Table 7.4 , frame 5
 leg .

(a) Global Reference System , leg 가 가 $a_X = 6.30$
 m/s^2 , $a_Y = 1.35 m/s^2$, $a_Z = -1.28 m/s^2$, knee X, Y, Z
 reaction force R_X, R_Y, R_Z .

(b) [G to A] matrix

(c) Local (anatomical) Reference System x, y, z
 $\omega_x, \omega_y, \omega_z$.

5. [4] Figure 8.7 Figure 8.8 muscle

(a) Figure 8.7 l_o

(b) Figure 8.8 F_p, F_c, F_t .

6. [4] Figure 9.6 Biological amplifier

(a) Gain 60dB 50dB , 가 1.5 mV signal
 amplifier output signal 가 가?

(b) amplifier가 filter Figure 9.8