Yeadon Configuration

For use with the yeadon python module by C. Dembia (fitze)

Notes/Key:

- denotes a joint centre is a vector into the page is a vector out of the page
- at the segment's joint centre.

Black vectors denote the local coordinate frame of the segment they are within. Despite the vectors' locations, the local coordinate systems of the segments are always have their origin Use the right-hand-rule on rotation vectors to determine the positive direction of the configuration variable. CA1rotation **CB1rotation CB1elevation** CA1elevation B1B2flexion A1A2flexion CA1abduction CB1abduction **TClateralSpinalFlexion TCspinalTorsion** PTfrontalFlexion X **PTsaggitalFlexion** somersalt tilt twist PK1abduction PJ1abduction PK1elevation x z/ PJ1elevation Κ1 11 J1J2flexion K1K2flexion

Yeadon, M. R. (1990c). The simulation of aerial movement-ii. a mathematical inertia model of the human body. Journal of Biomechanics, 23:67-74.