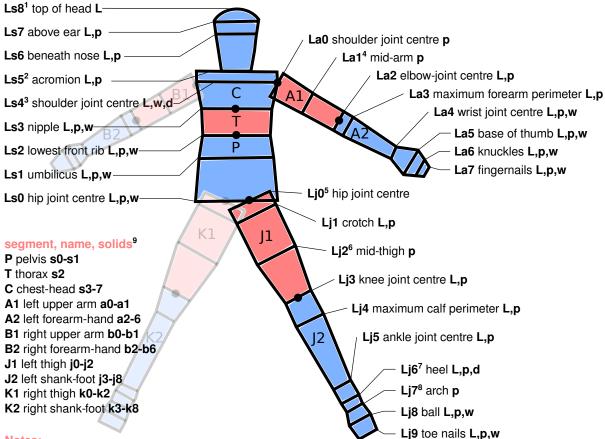
Yeadon Measurements For use with the yeadon python module by C. Dembia (fitze)

- denotes a joint centre
- L (on the left) denotes a level at which a stadium solid or circle is defined (except for Ls8)
- L (on the right) denotes a length measurement
 - Ls1L-Ls5L measured from Ls0; Ls6L-Ls8L measured from Ls5L
 - La2L-La4L measured from La0; La5L-La7L measured from La4L (some for b)
 - Lj1L,Lj3-5L measured from Lj0; Lj6L,Lj8L-Lj9L measured from Lj5L (same for k)
- **p** denotes a perimeter measurement, must have 2w < p < pi*w
- w denotes a width (medio-lateral, or side to side) measurement
- d denotes a depth (anterior-posterior, or front to back) measurement

level, name, measurements needed



Notes:

Total mass can be measured and provided to "correct" the densities used.

- 1 s0 is the only semi-ellipsoidal solid (with circular cross section)
- 2 two stadia at this level, one for s4 and one for s5. s4 stadium's parameters are calculated from Ls4's stadium. Ls5 perimeter measured around neck
- 3 depth is measured in lieu of perimeter since arms interfere
- 4 La1L is set as half of La2L
- 5 stadium (circle) parameter calculated from Ls0's stadium
- 6 Lj2L is set as the average of Lj1L and Lj3L
- 7 Li6's (and Lk6's) stadia are the only stadium oriented anterior-posteriorly
- 8 Li7L is set as the average of Li6L and Li8L
- 9 Yeadon's 1990 paper indexes the solids from 1, while this formulations indexes from 0

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

Unit conversion

Name:	Date:
ivallie.	Dale.

measToMeters (number to convert from measurement units into meters):

Measurement input

weasurement input		
Torso	Left arm	Right arm
Ls1L:	La2L:	Lb2L:
Ls2L:	La3L:	Lb3L:
Ls3L:	La4L:	Lb4L:
Ls4L:	La5L:	Lb5L:
Ls5L:	La6L:	Lb6L:
Ls6L:	La7L:	Lb7L:
Ls7L:		
Ls8L:	La0p:	Lb0p:
	La1p:	Lb1p:
Ls0p:	La2p:	Lb2p:
Ls1p:	La3p:	Lb3p:
Ls2p:	La4p:	Lb4p:
Ls3p:	La5p:	Lb5p:
Ls4p:	La6p:	Lb6p:
Ls5p:	La7p:	Lb7p:
Ls6p:	·	•
Ls7p:	La4w:	Lb4w:
Ls8p:	La5w:	Lb5w:
·	La6w:	Lb6w:
Ls0w:	La7w:	Lb7w:
Ls1w:		
Ls2w:	Left leg	Right leg
Ls3w:	Lj1L:	Lk1L:
Ls4w:	Lj3L:	Lk3L:
	Lj4L:	Lk4L:
Ls4d:	Lj5L:	Lk5L:
	Lj6L:	Lk6L:
Density Correction	Lj8L:	Lk8L:
to ignore, set to 0	Lj9L:	Lk9L:
Total mass (kg):	•	
, ,,	Lj0p:	Lk0p:
	Lj1p:	Lk1p:
	Lj2p:	Lk2p:
	Lj3p:	Lk3p:
	Lj4p:	Lk4p:
	Lj5p:	Lk5p:
	Lj6p:	Lk6p:
	Lj7p:	Lk7p:
	Lj8p:	Lk8p:
	Lj9p:	Lk9p:
	Lj8w:	Lk8w:
	Lj9w:	Lk9w:
	Lj6d:	Lk6w: