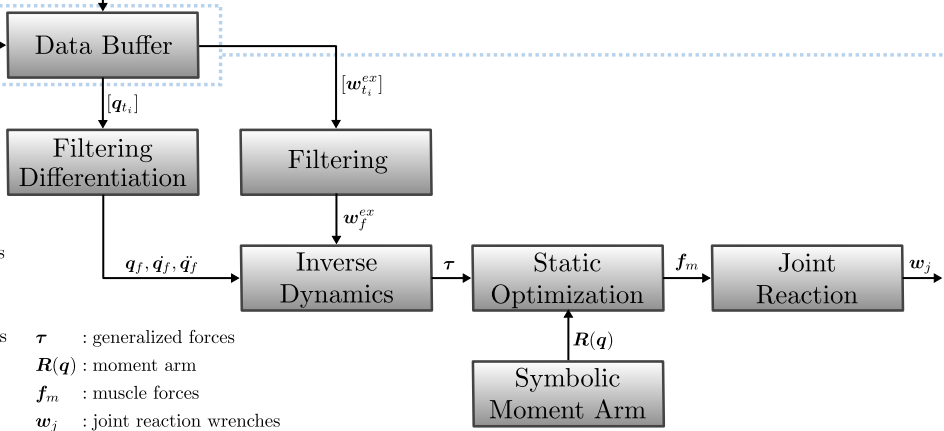


Acquisition Thread



Processing Thread

x^m : measured marker positions
 x_r^m : reconstructed marker positions
 θ : sensor orientations
 q : generalized coordinates
 $[q_{t_i}]$: buffered generalized coordinates
 q_f : filtered generalized coordinates
 \dot{q}_f : filtered generalized velocities
 \ddot{q}_f : filtered generalized accelerations
 w^{ex} : external wrenches
 $[w_{t_i}^{ex}]$: buffered external wrenches
 w_f^{ex} : filtered external wrenches



τ : generalized forces
 $R(q)$: moment arm
 f_m : muscle forces
 w_j : joint reaction wrenches