

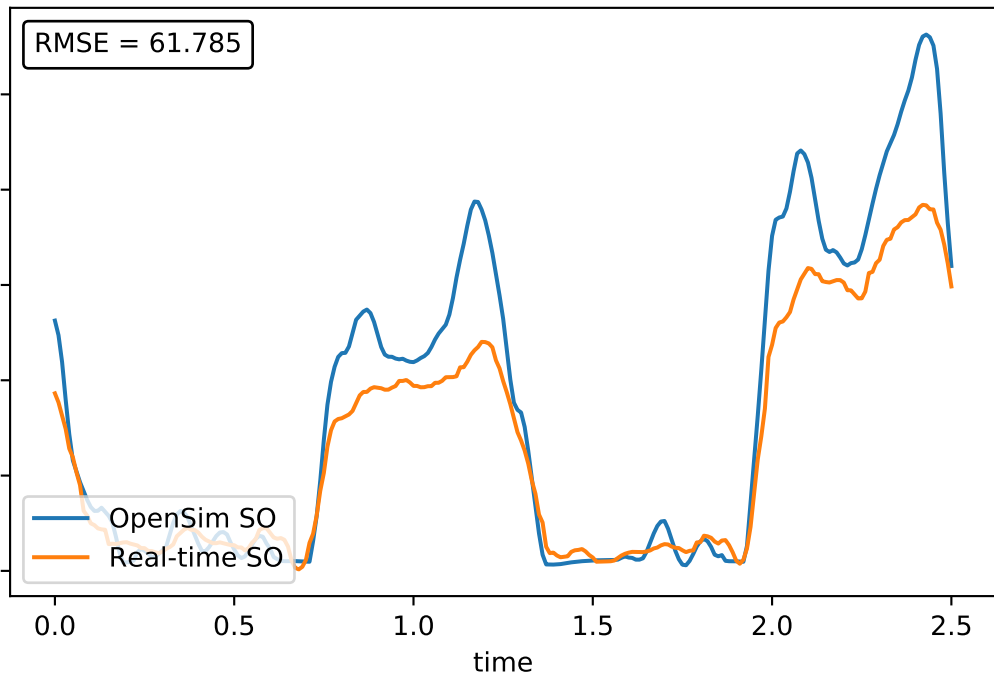
# glut\_med1\_r

RMSE = 61.785

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



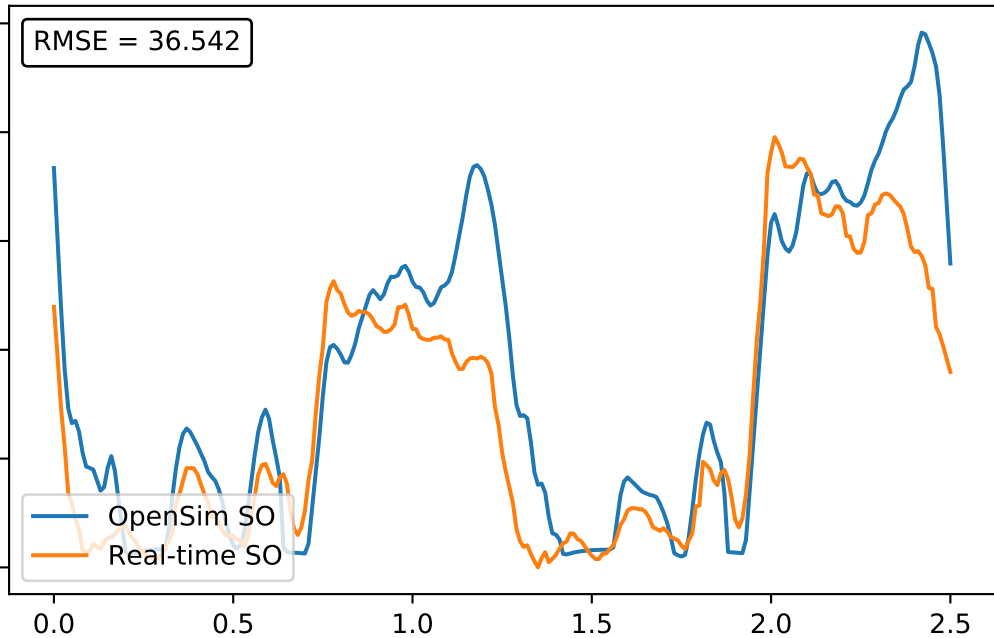
# glut\_med2\_r

RMSE = 36.542

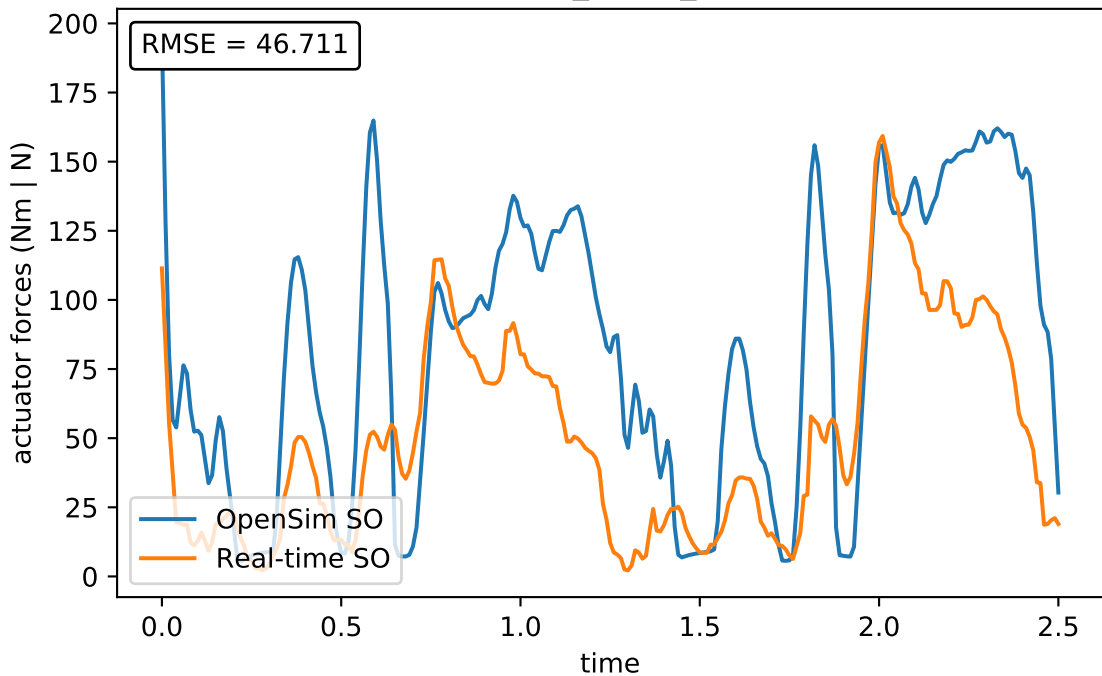
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



# glut\_med3\_r



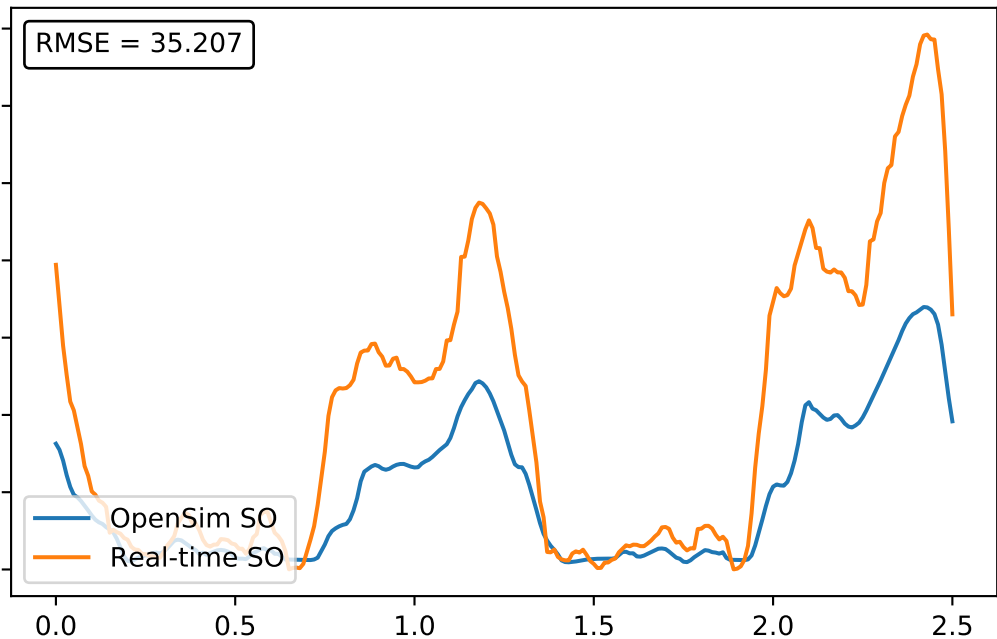
# glut\_min1\_r

RMSE = 35.207

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



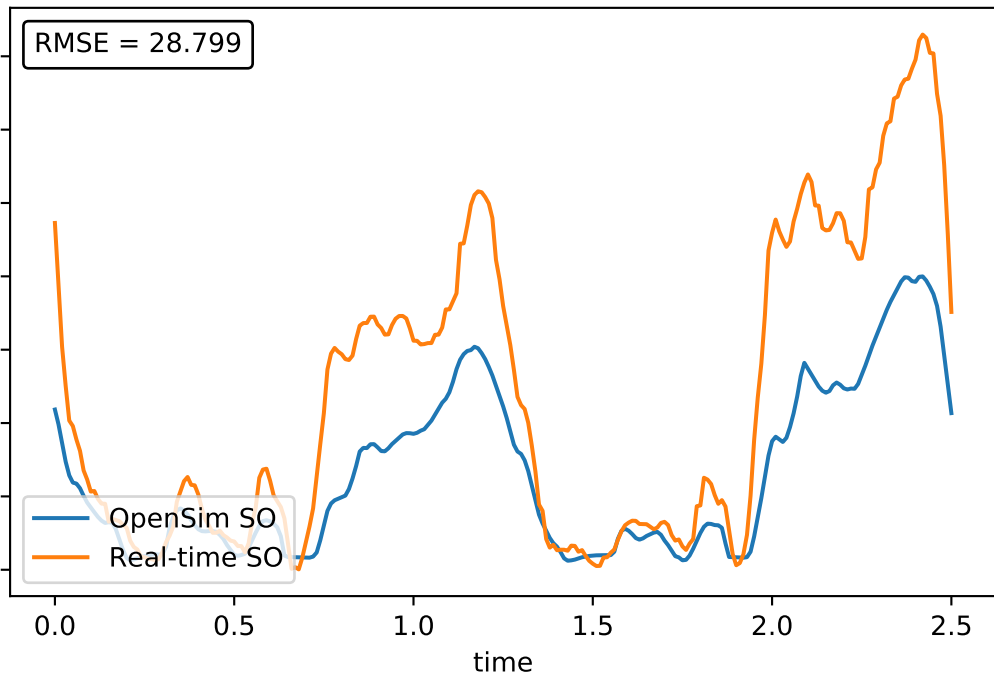
# glut\_min2\_r

RMSE = 28.799

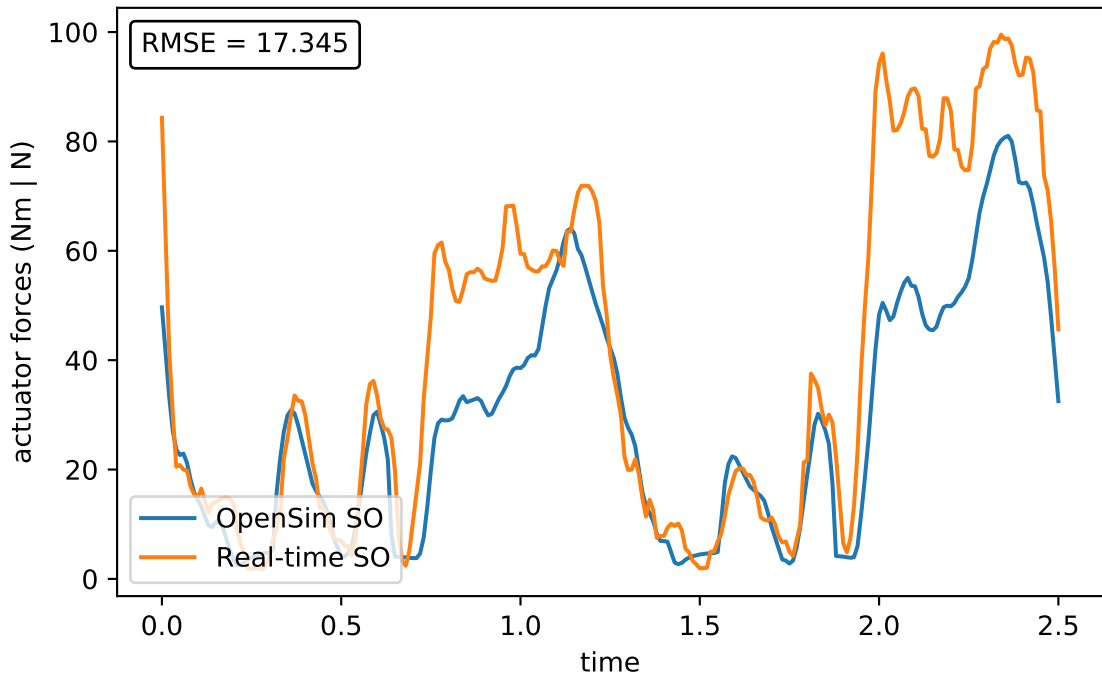
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

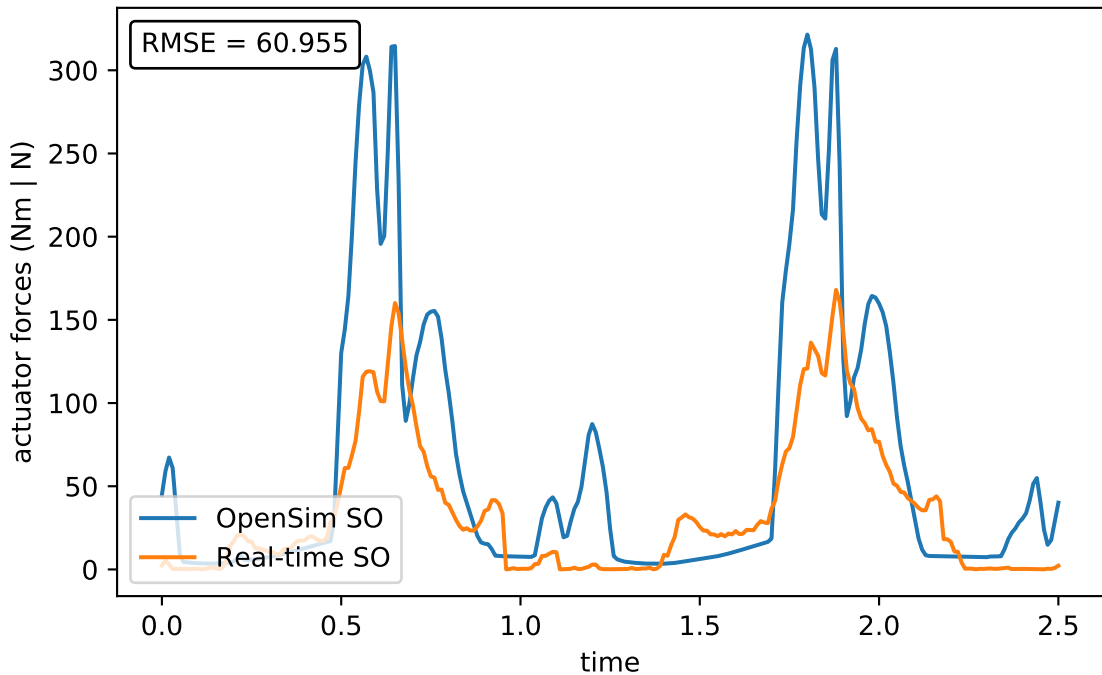
time



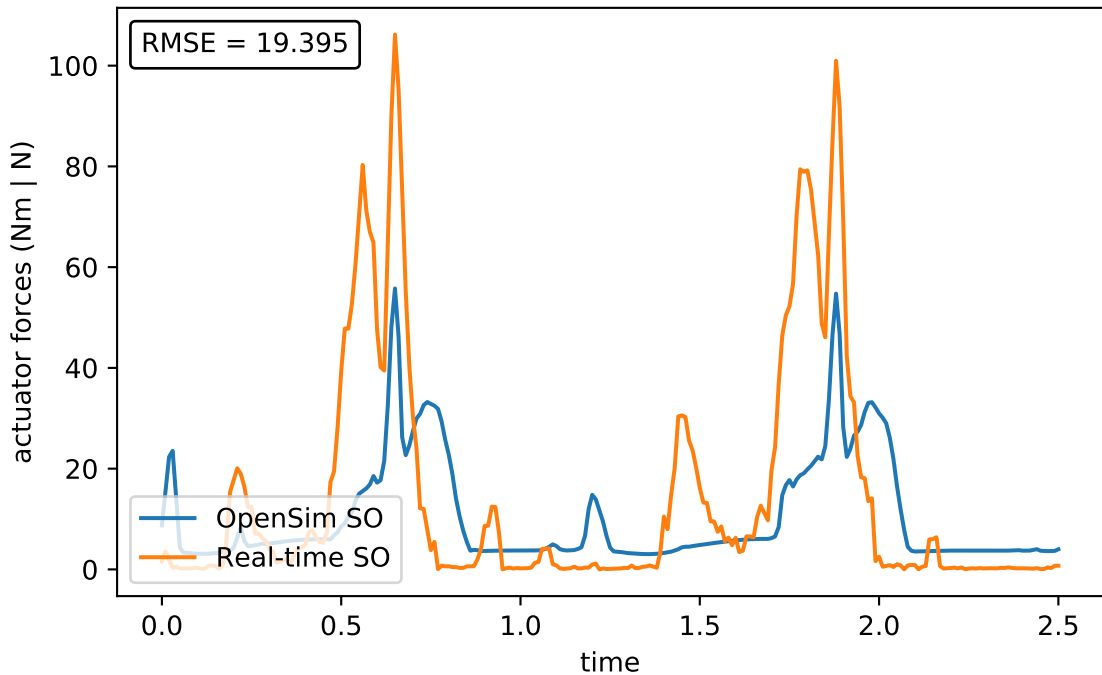
# glut\_min3\_r



# semimem\_r

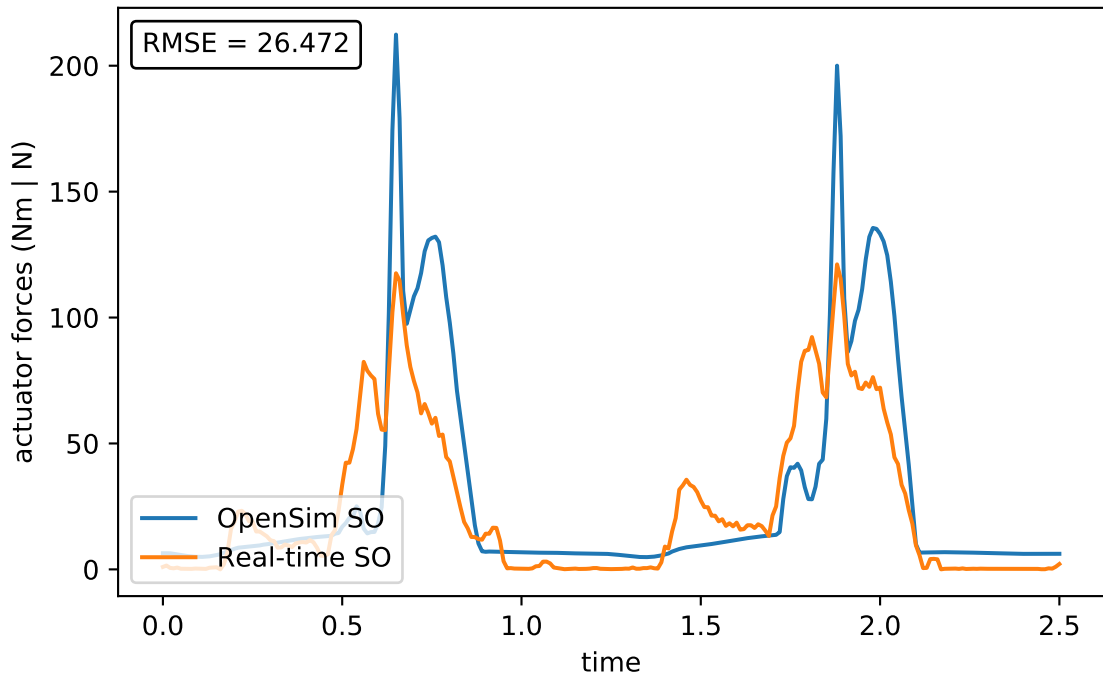


# semiten\_r





# bifemlh\_r



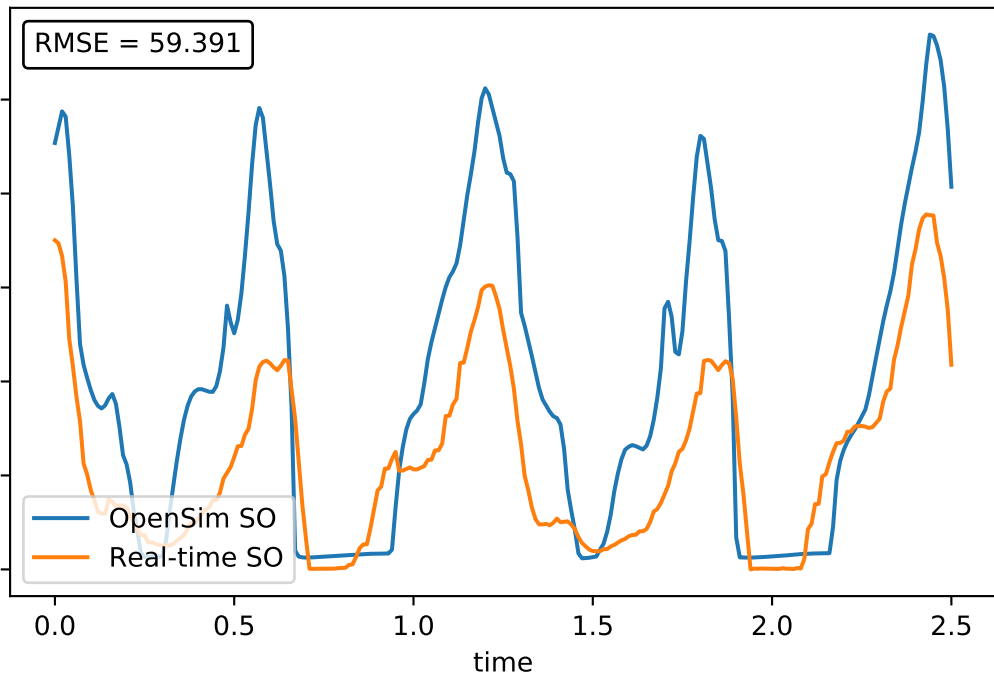
# bifemsh\_r

RMSE = 59.391

actuator forces (Nm | N)

— OpenSim SO  
— Real-time SO

time



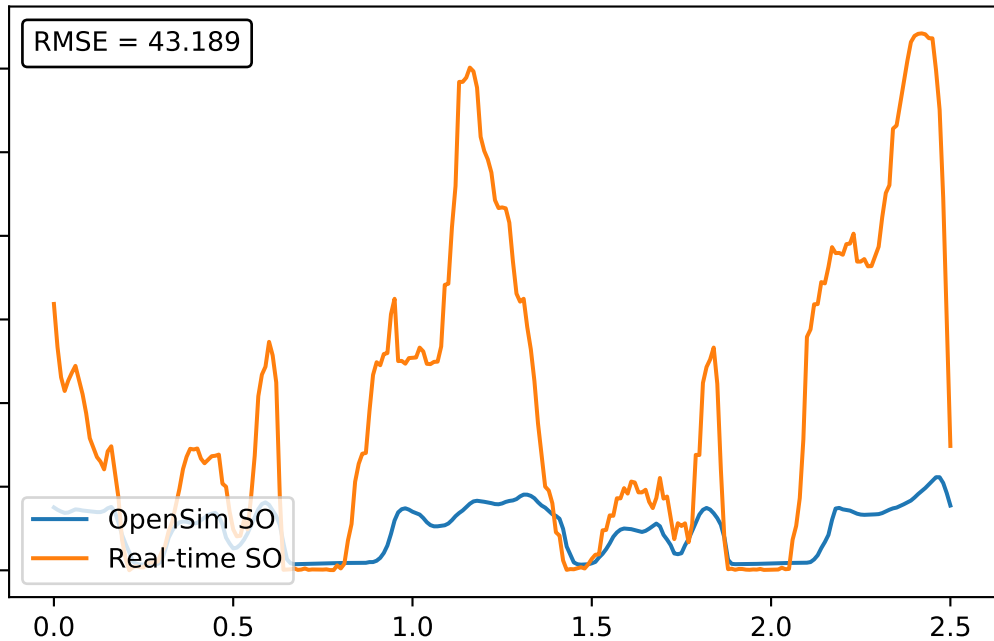
sar\_r

RMSE = 43.189

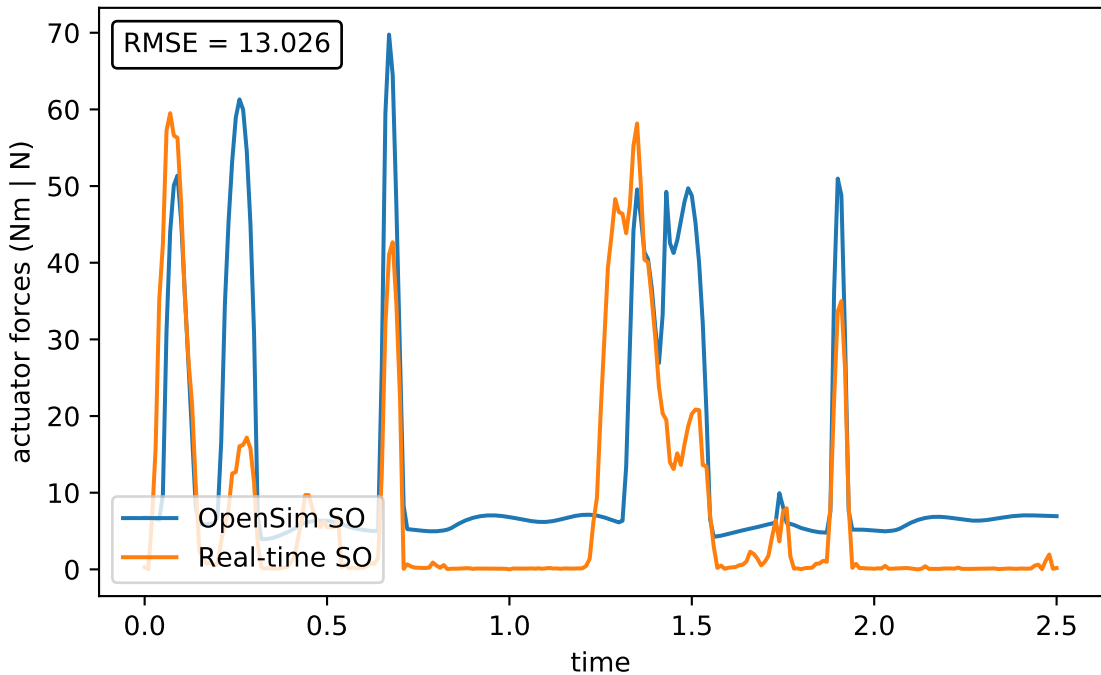
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

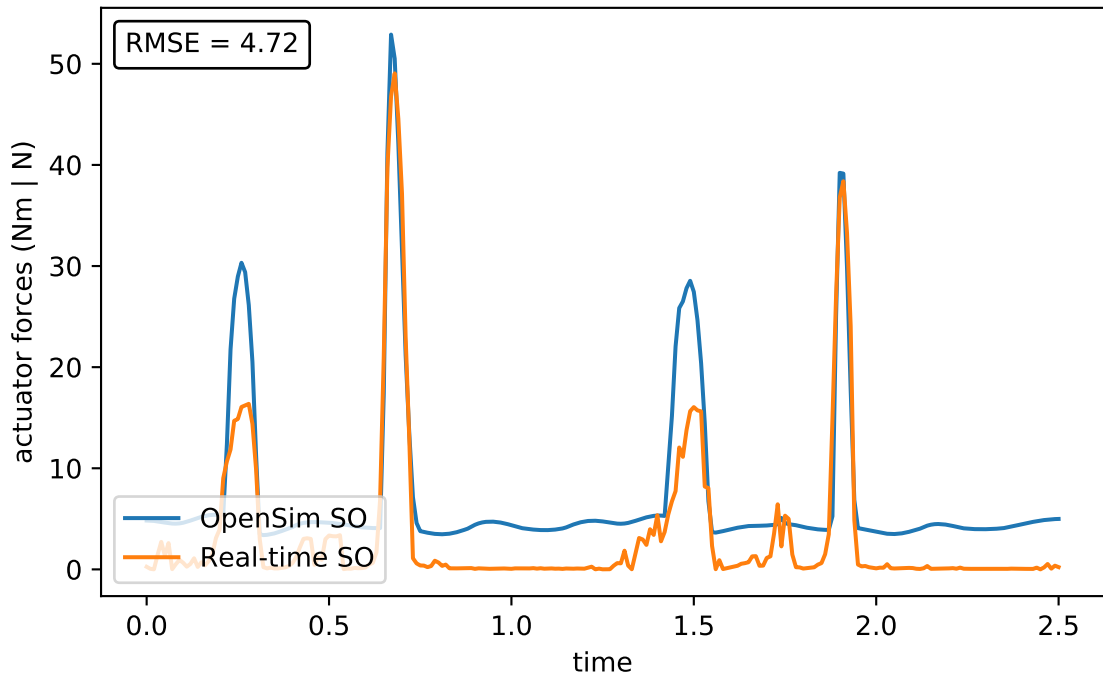
time



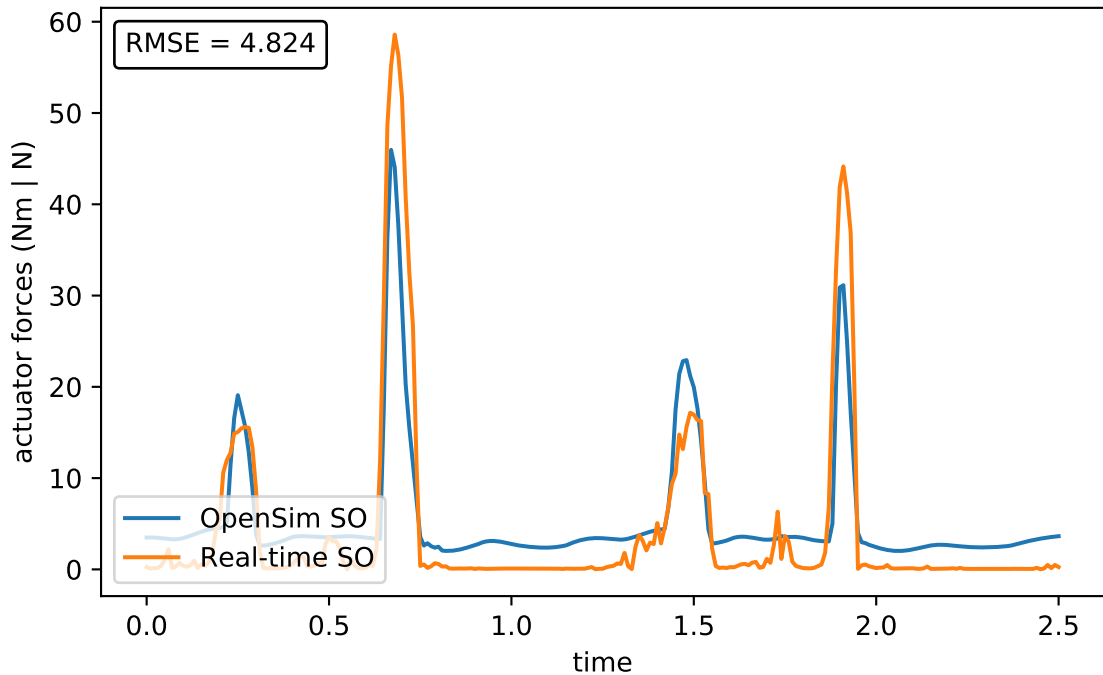
## add\_long\_r



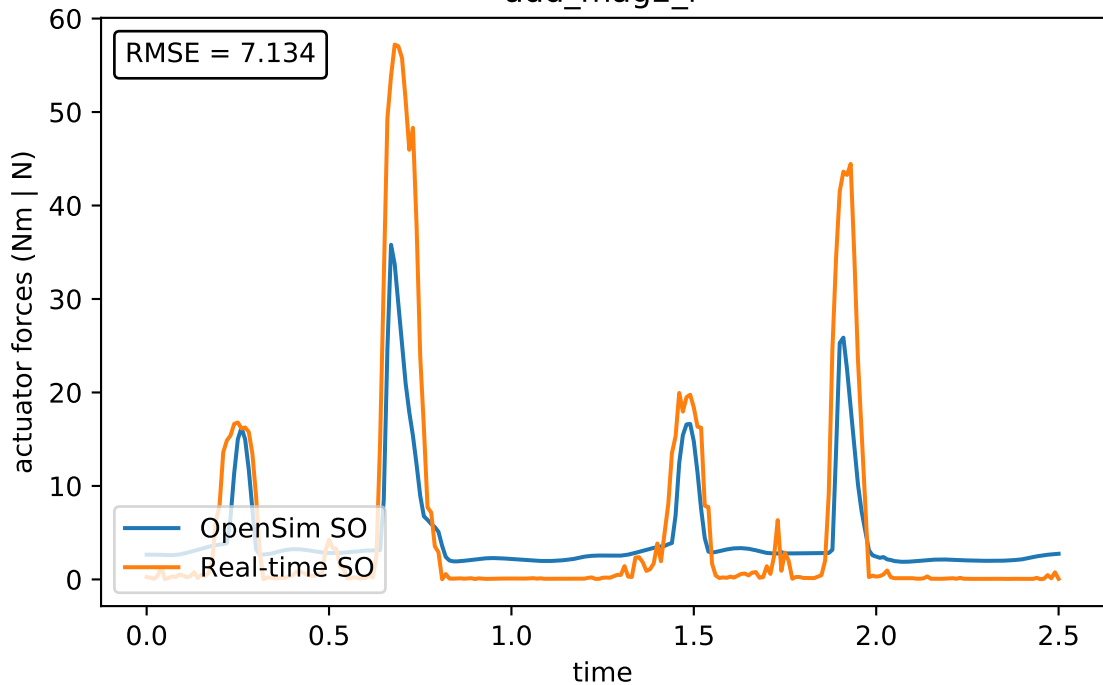
# add\_brev\_r



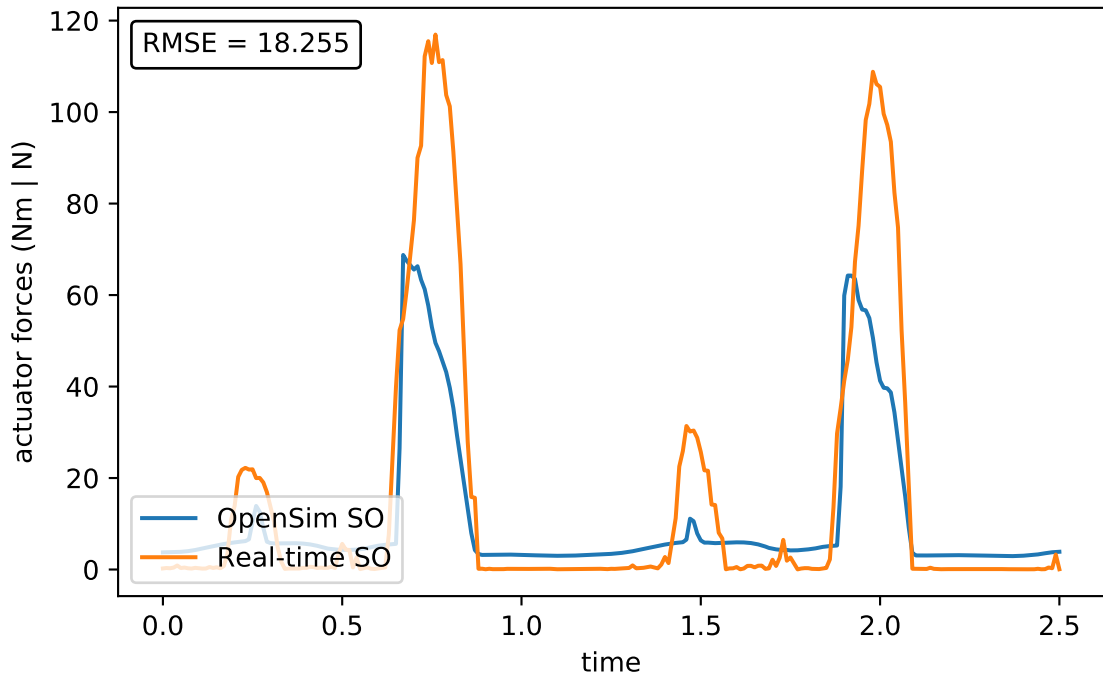
# add\_mag1\_r



## add\_mag2\_r



# add\_mag3\_r





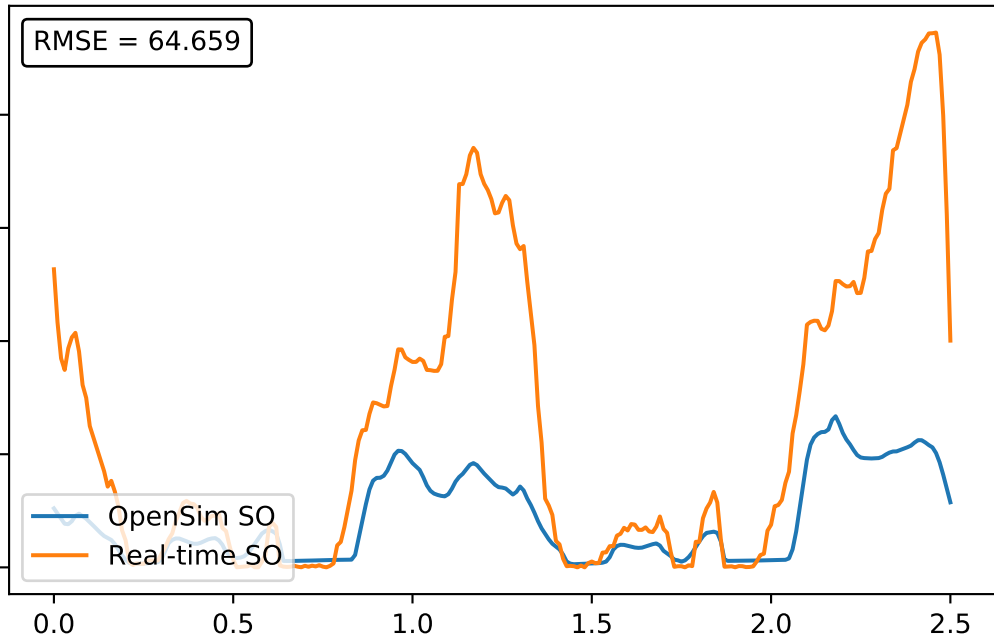
tfl\_r

RMSE = 64.659

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



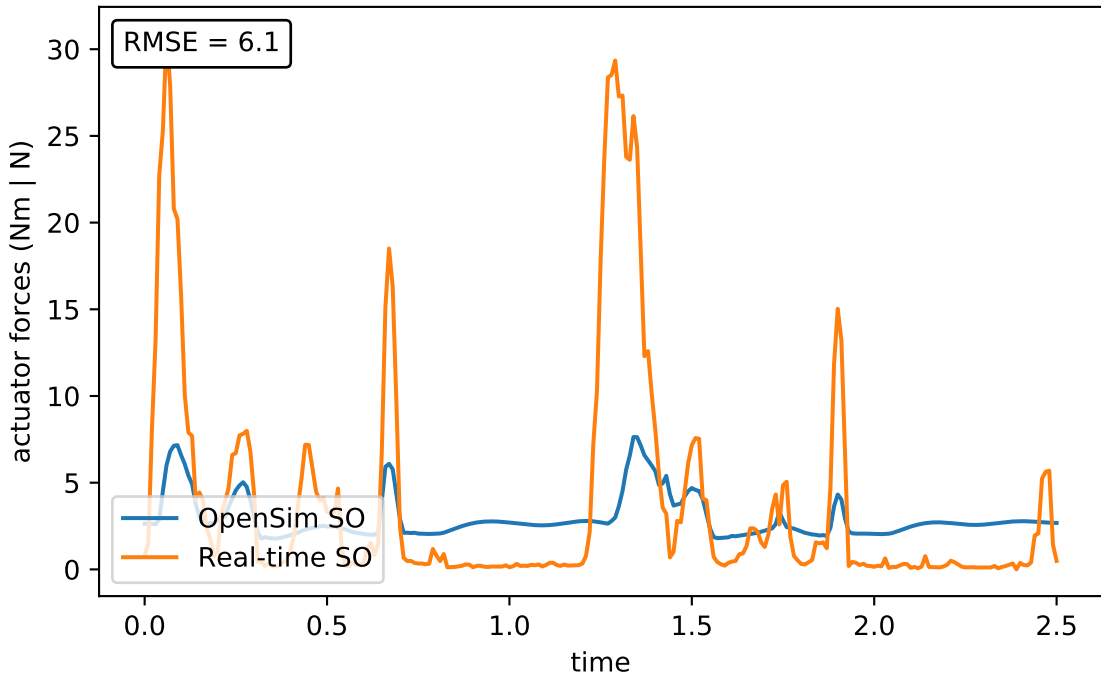
pect\_r

RMSE = 6.1

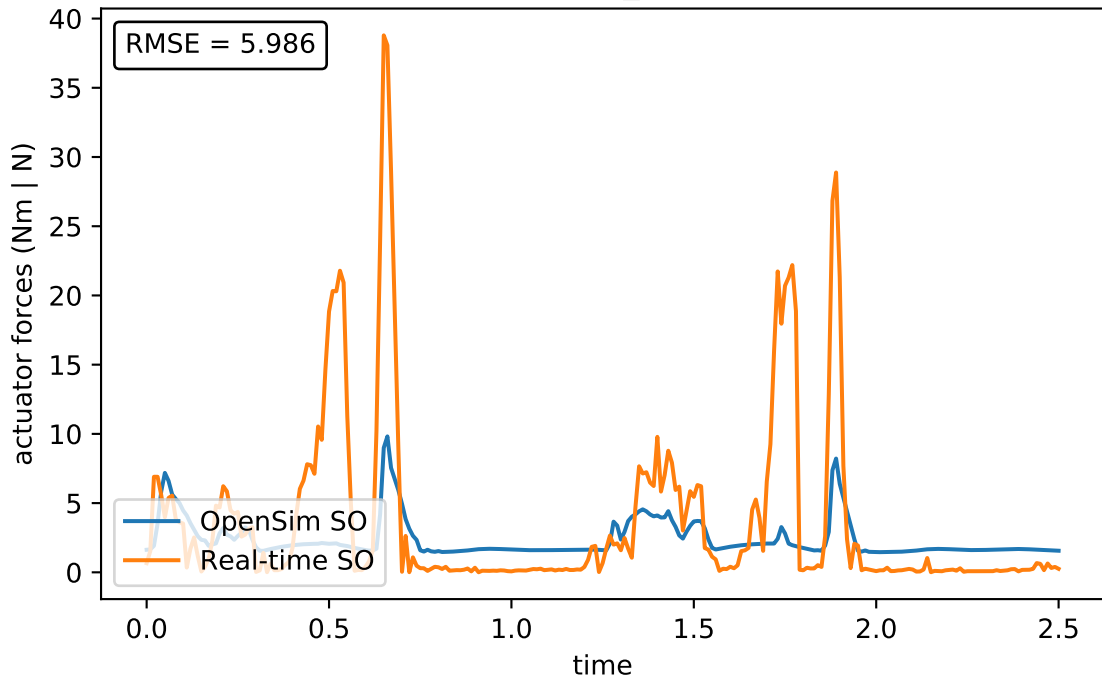
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

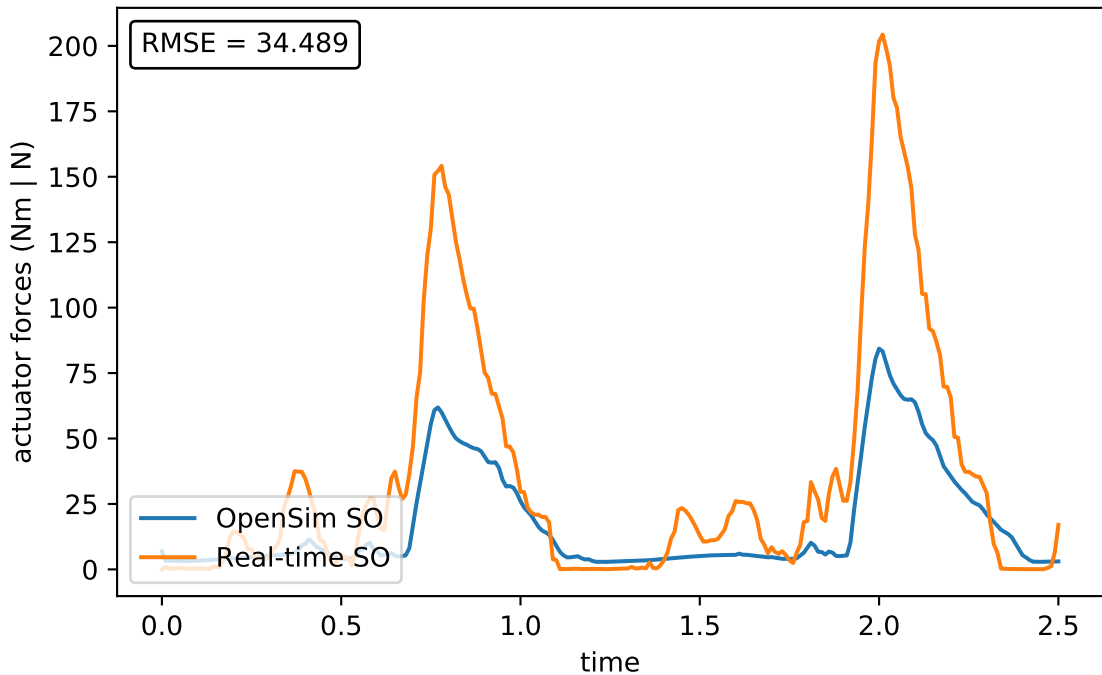
time



# grac\_r



glut\_max1\_r



# glut\_max2\_r

RMSE = 19.572

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0

0.5

1.0

1.5

2.0

2.5

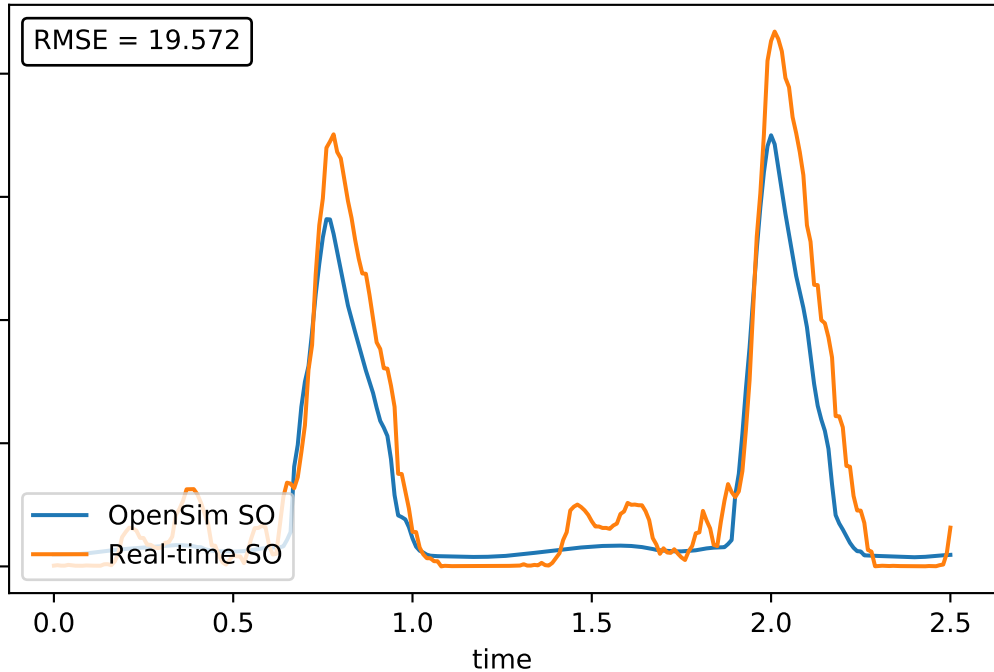
200

150

100

50

0



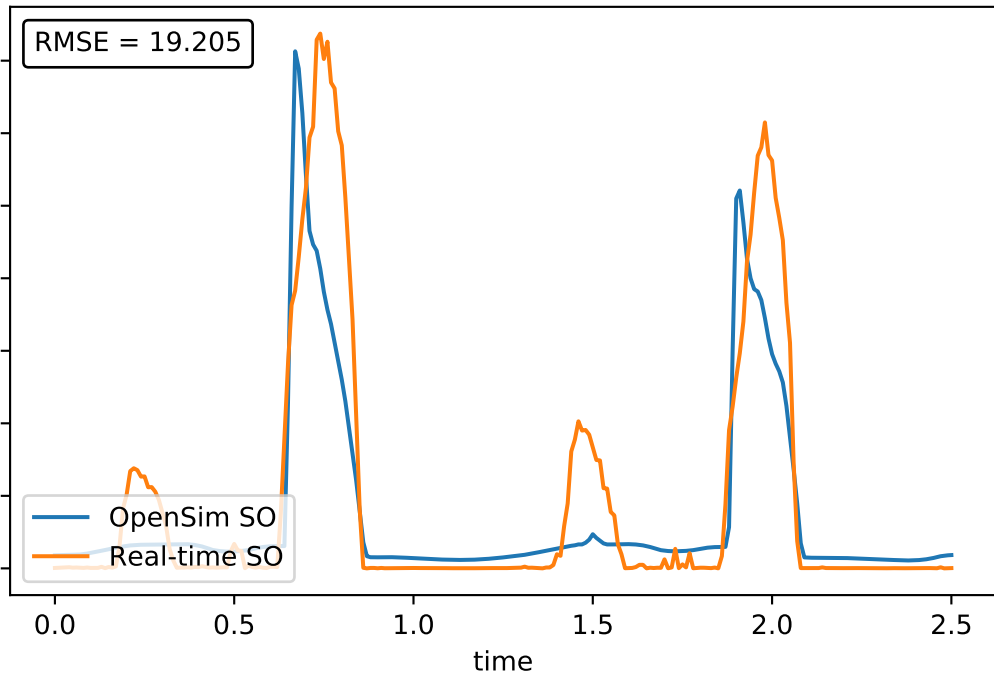
# glut\_max3\_r

RMSE = 19.205

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



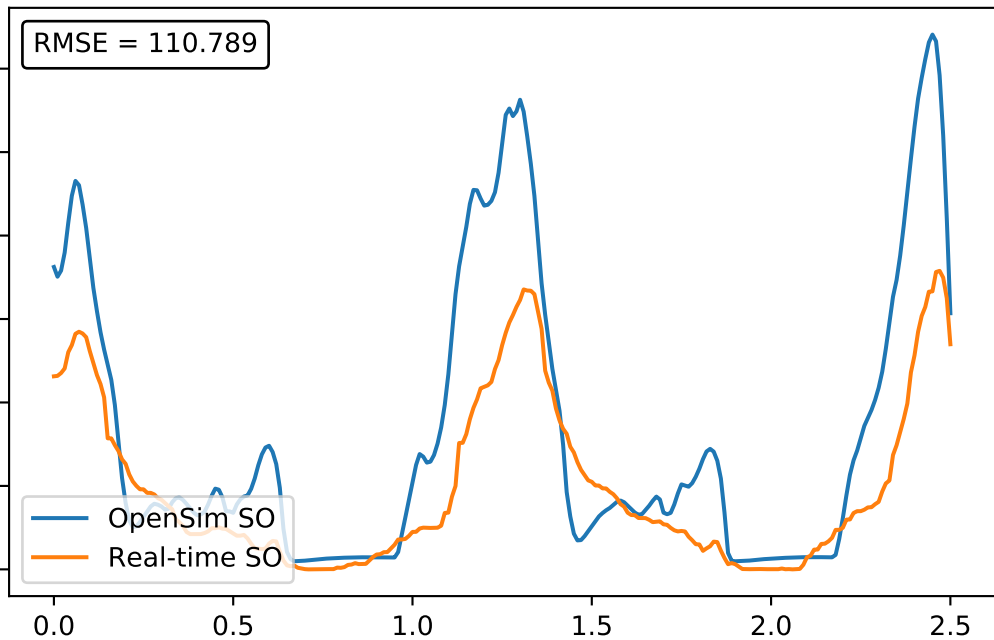
# iliacus\_r

RMSE = 110.789

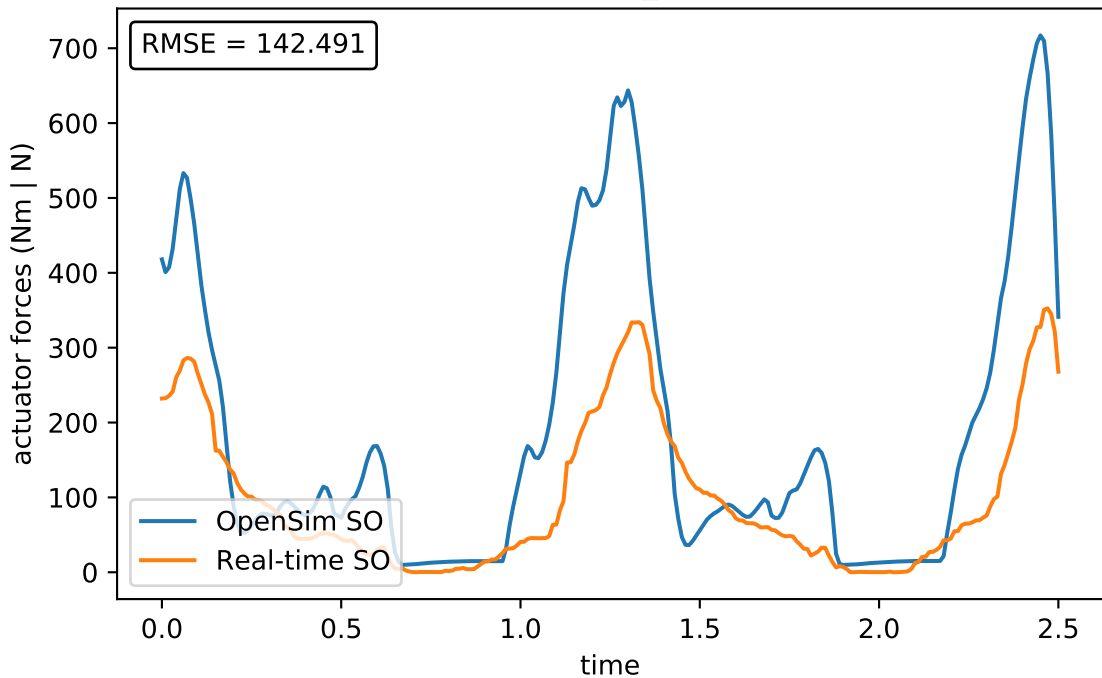
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



# psoas\_r





# quad\_fem\_r

RMSE = 8.057

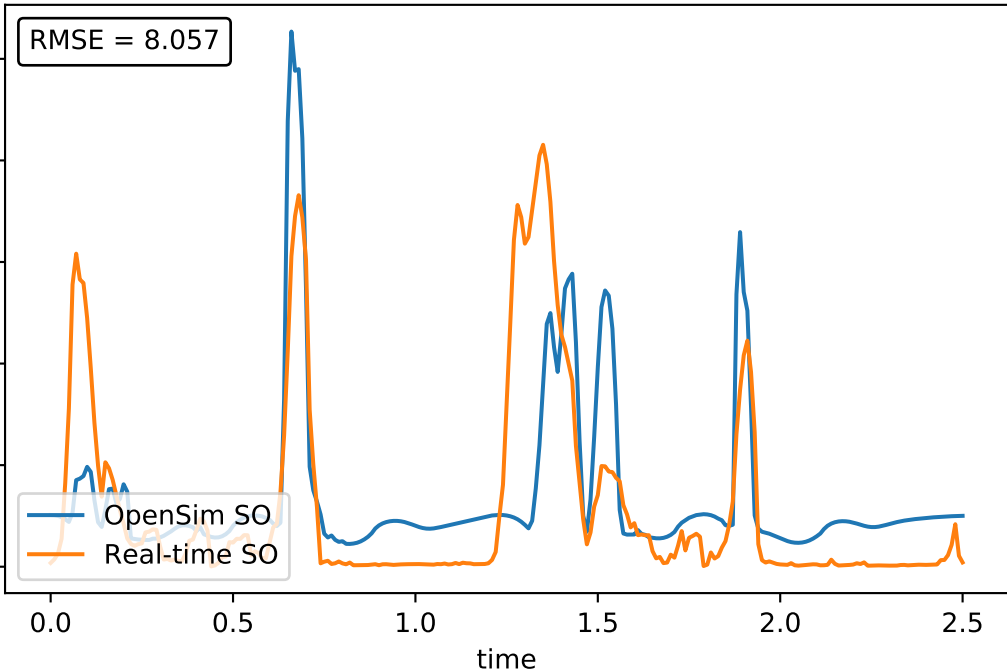
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

50  
40  
30  
20  
10  
0



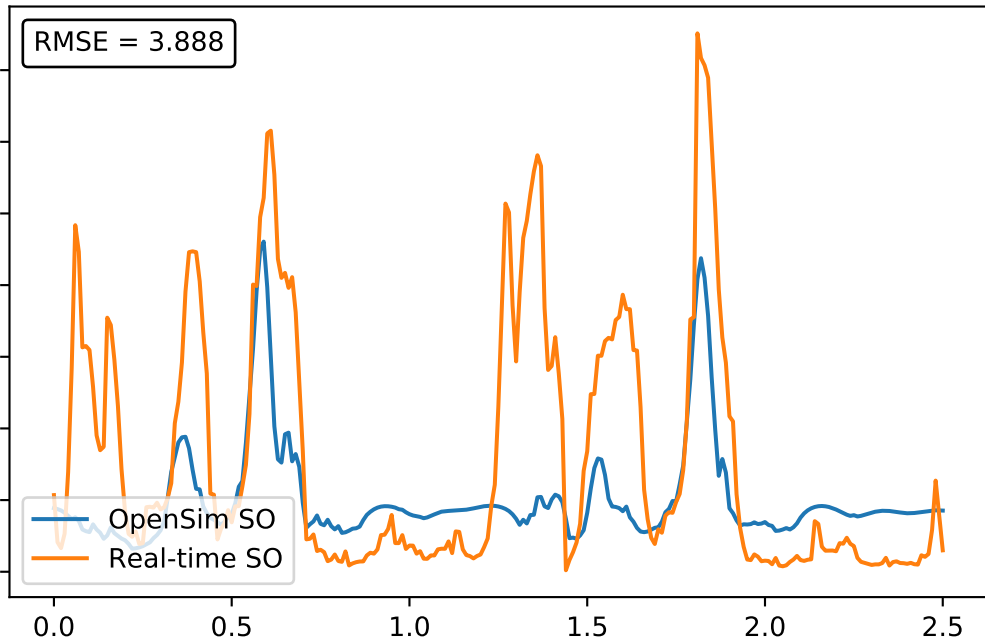
# gem\_r

RMSE = 3.888

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



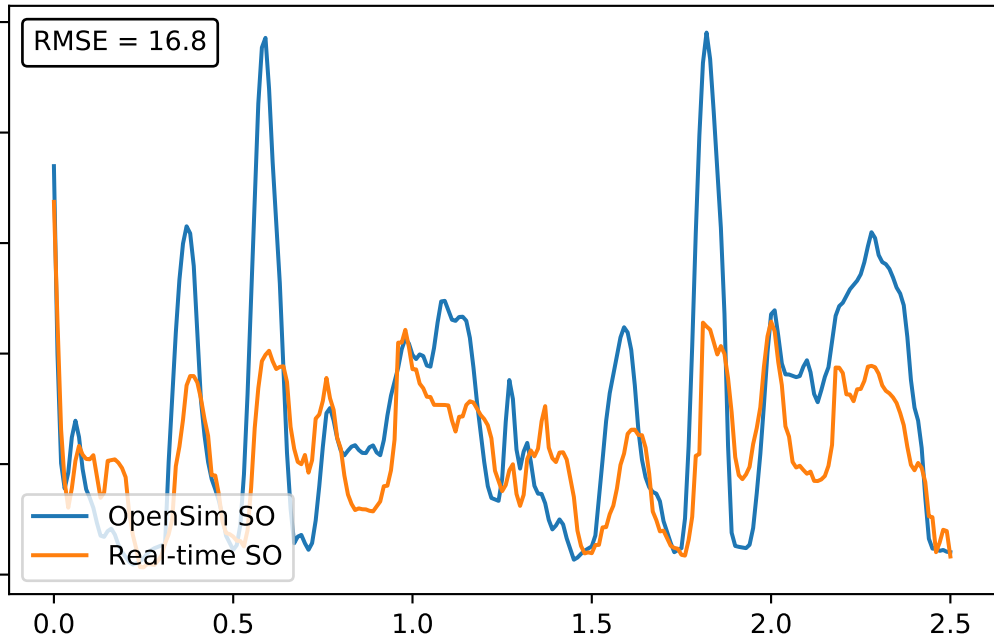
peri\_r

RMSE = 16.8

actuator forces (Nm | N)

— OpenSim SO  
— Real-time SO

time



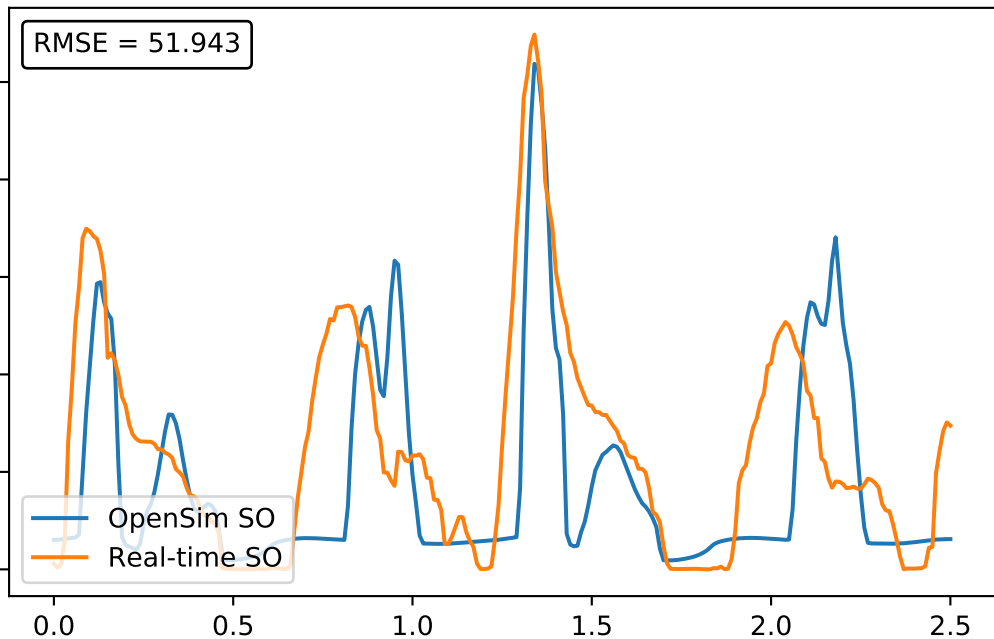
# rect\_fem\_r

RMSE = 51.943

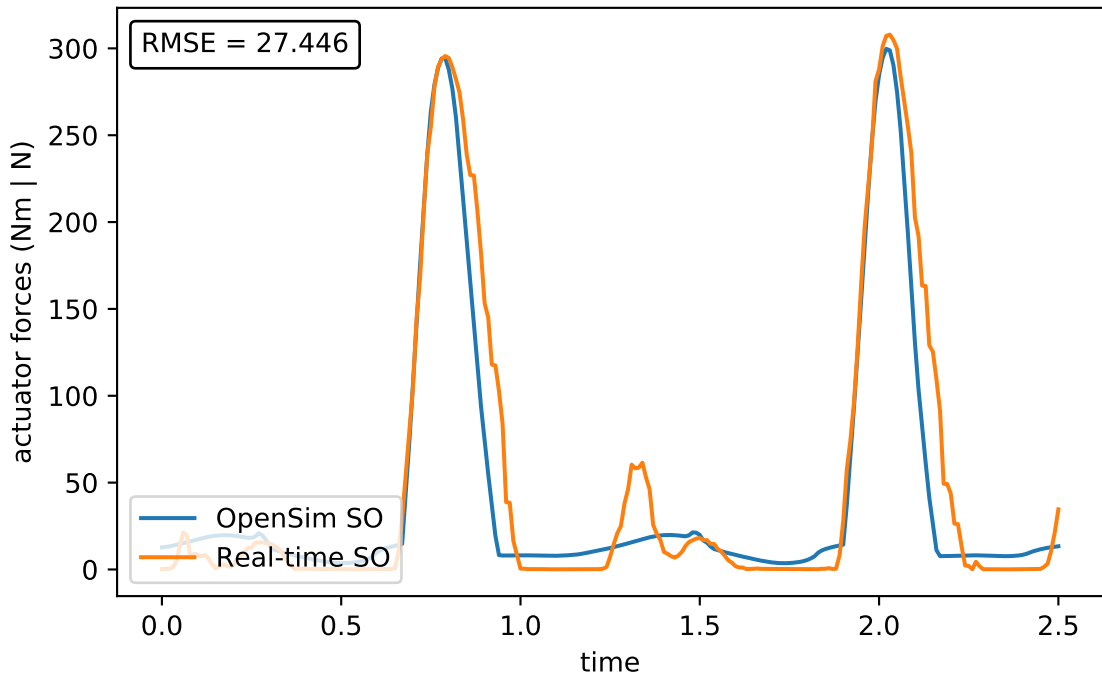
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

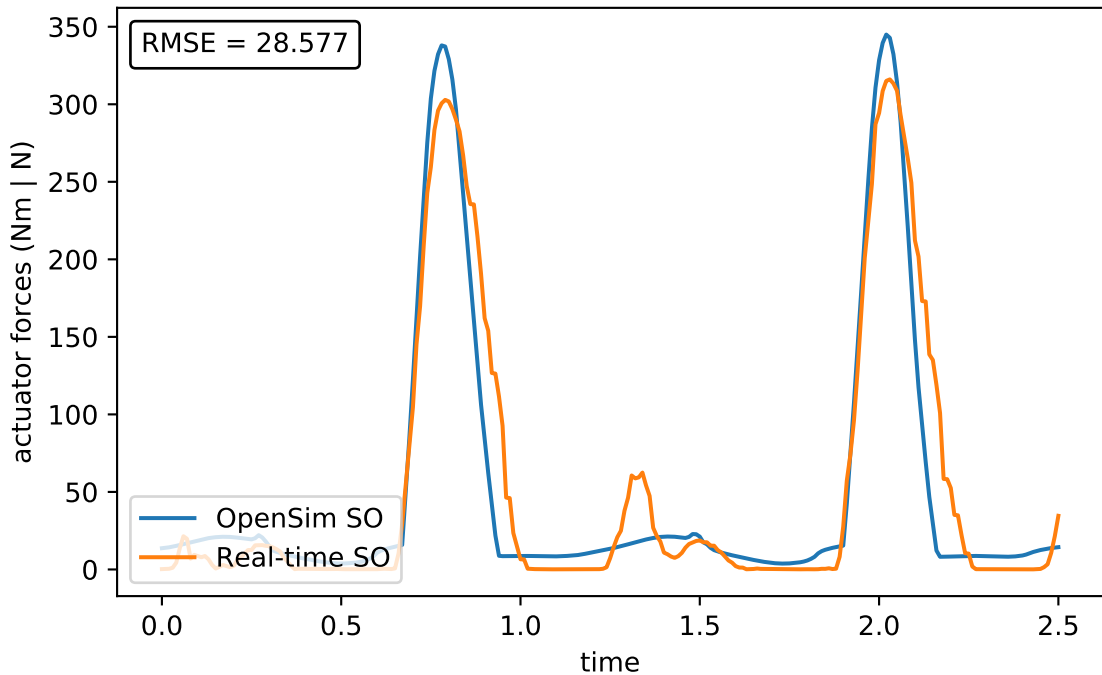
time



# vas\_med\_r



# vas\_int\_r



# vas\_lat\_r

RMSE = 91.626

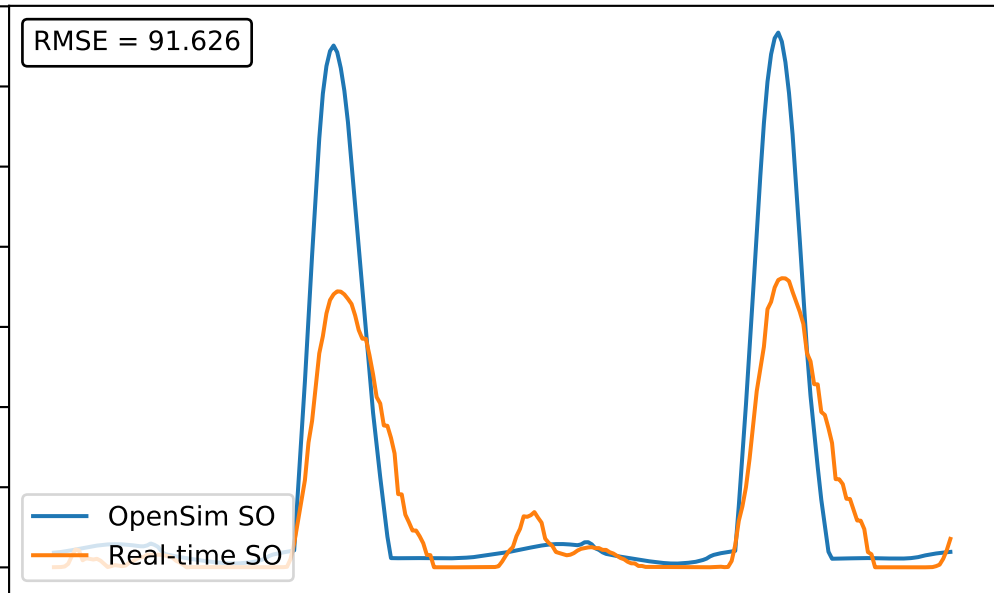
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

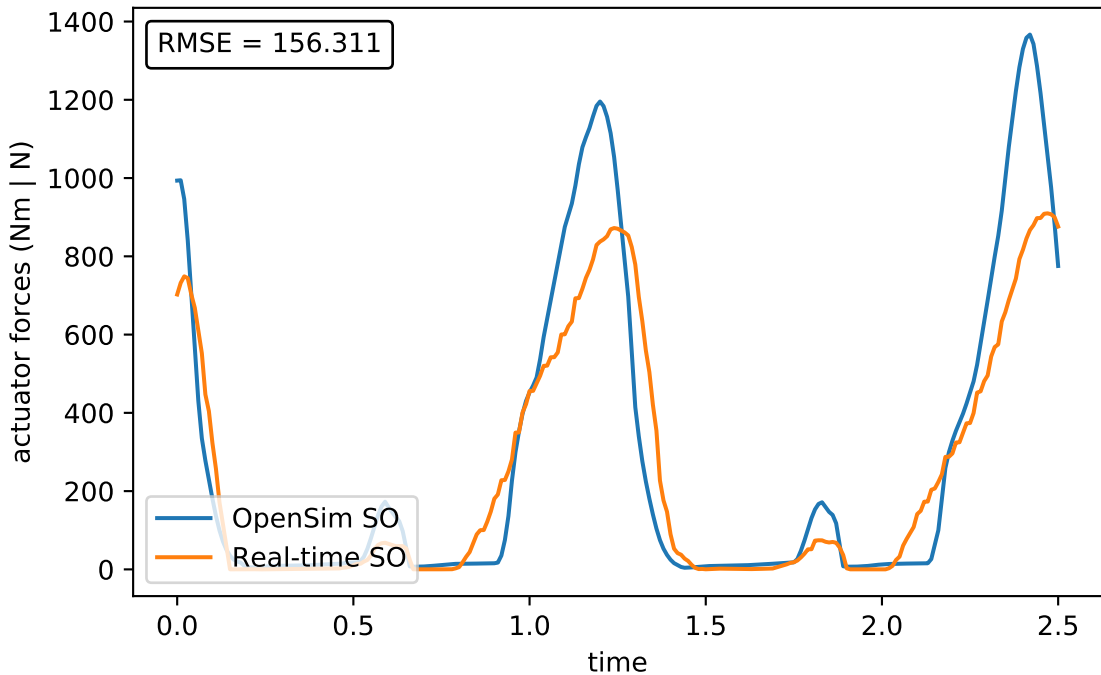
time

0.0 0.5 1.0 1.5 2.0 2.5

700  
600  
500  
400  
300  
200  
100  
0



# med\_gas\_r





lat\_gas\_r

RMSE = 139.647

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0

0.5

1.0

1.5

2.0

2.5

600

500

400

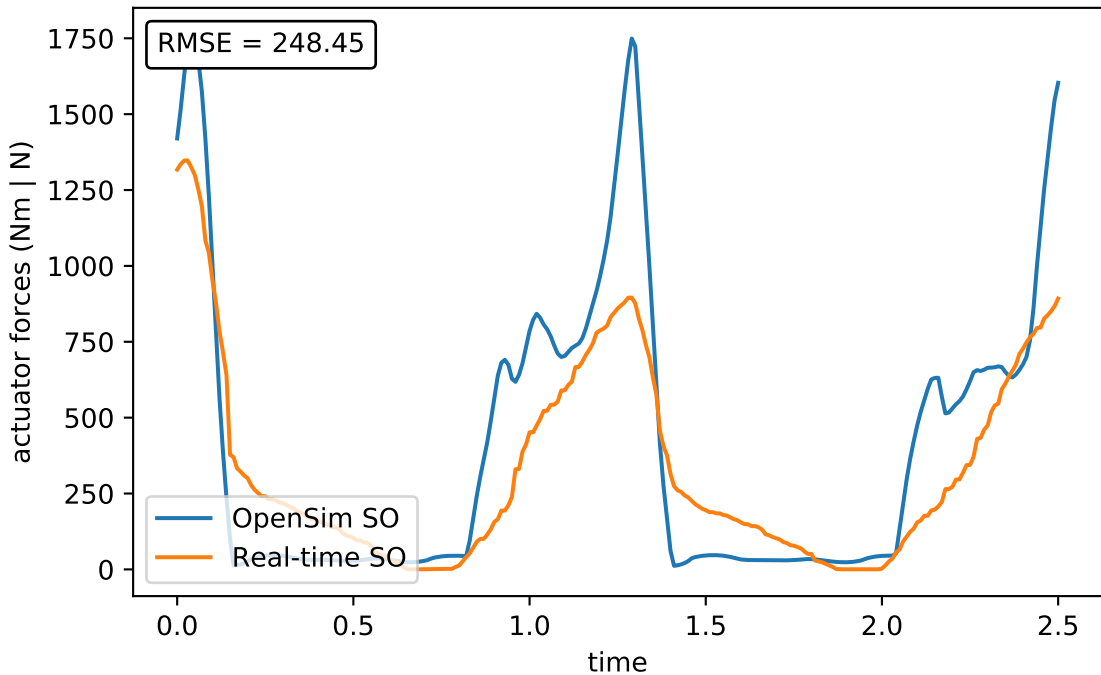
300

200

100

0

# soleus\_r



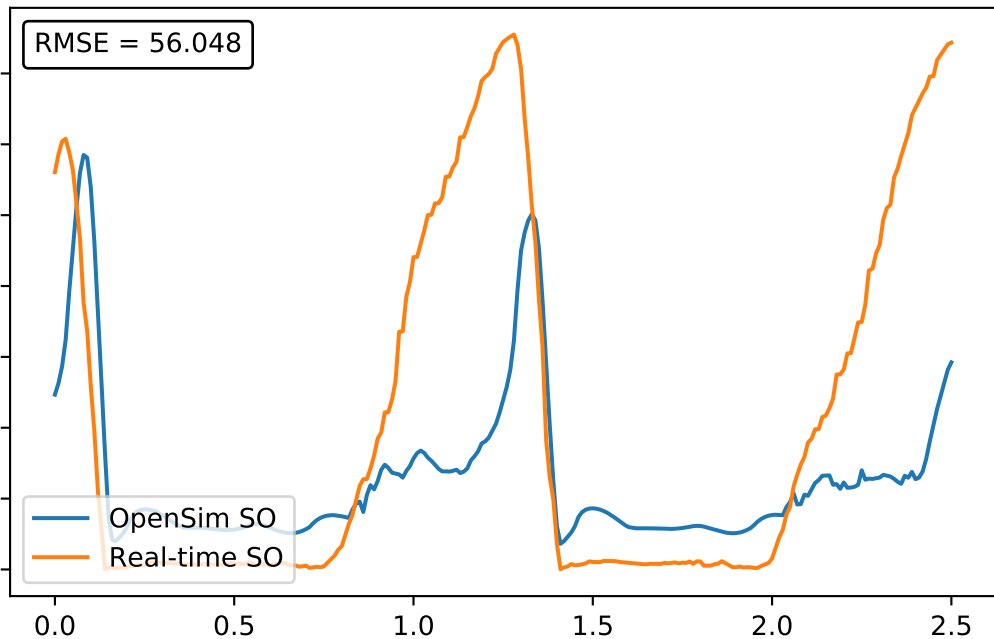
# tib\_post\_r

RMSE = 56.048

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



# flex\_dig\_r

RMSE = 21.909

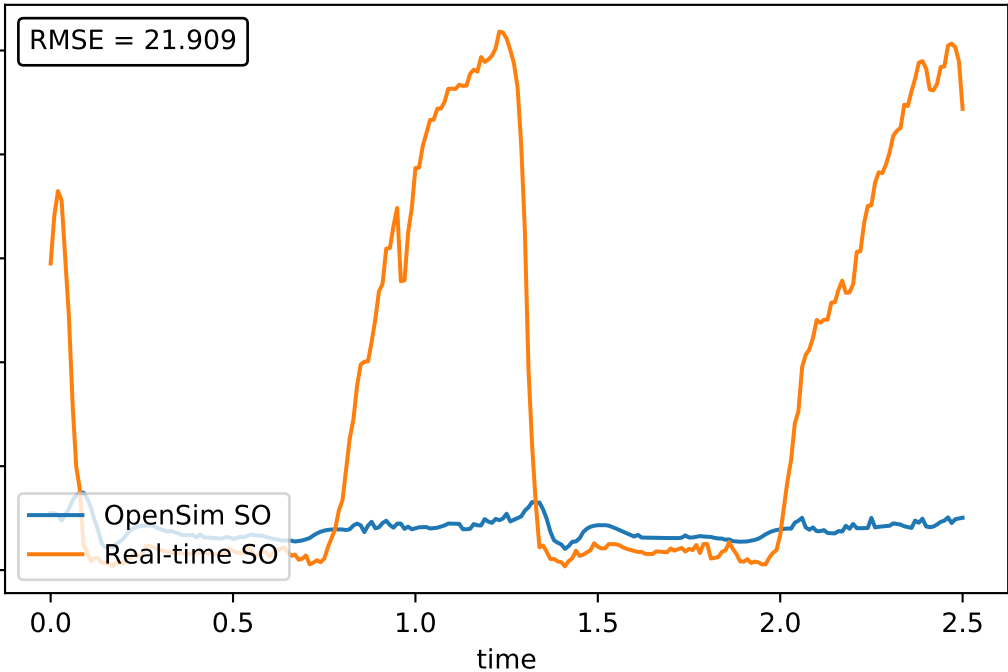
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

50  
40  
30  
20  
10  
0



# flex\_hal\_r

RMSE = 31.215

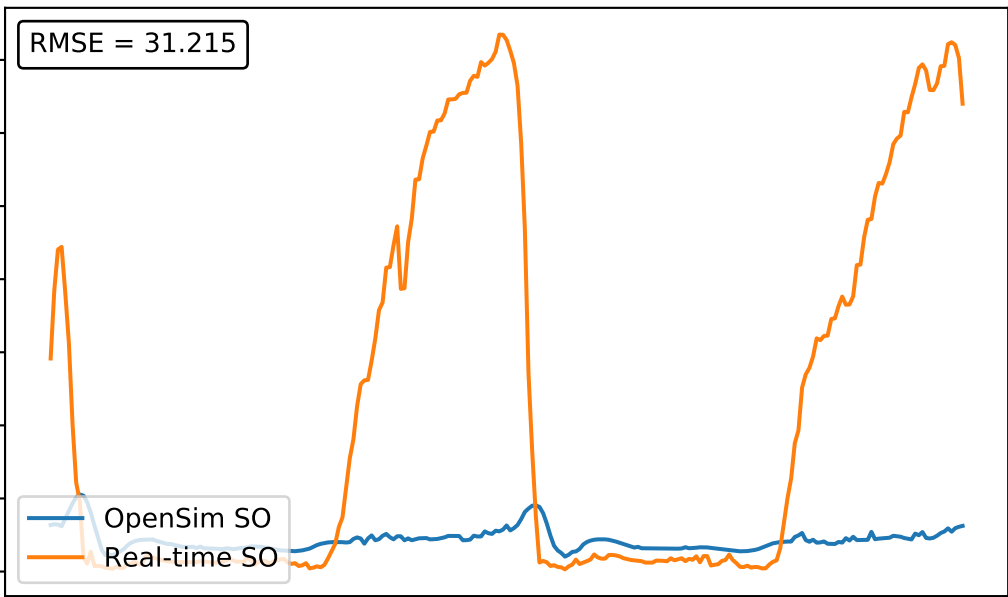
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

70  
60  
50  
40  
30  
20  
10  
0



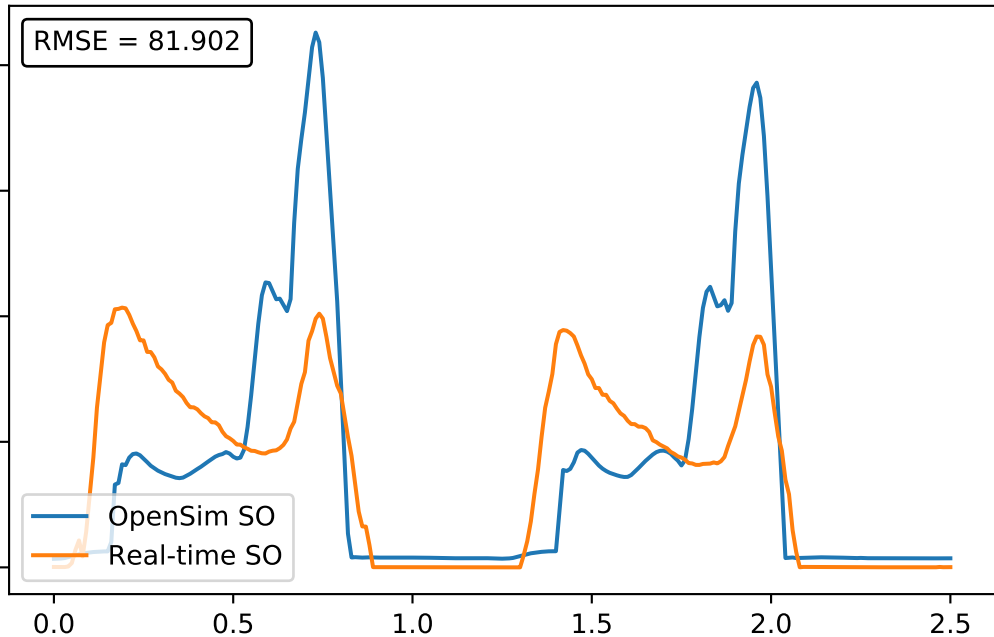
# tib\_ant\_r

RMSE = 81.902

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



per\_brev\_r

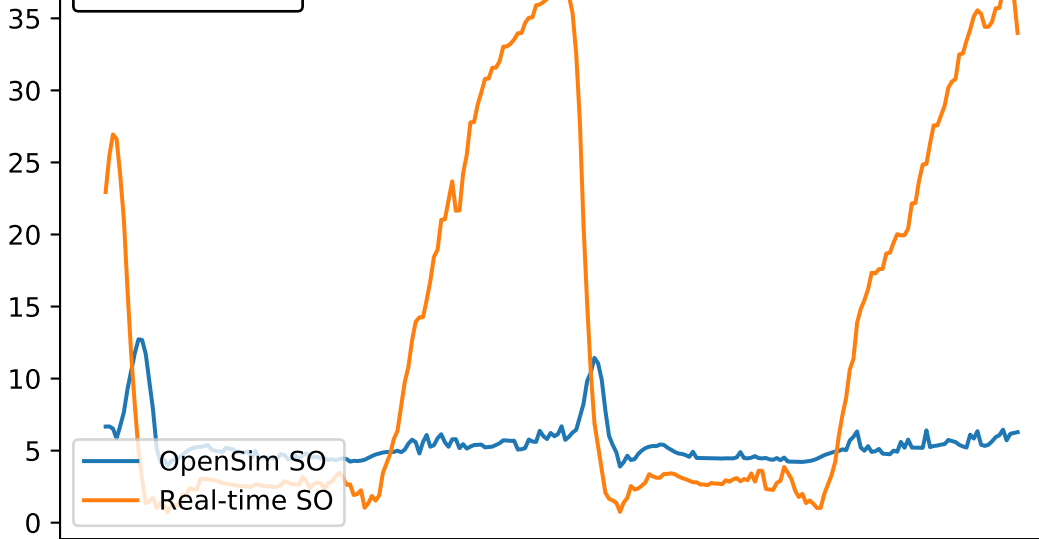
RMSE = 14.658

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5



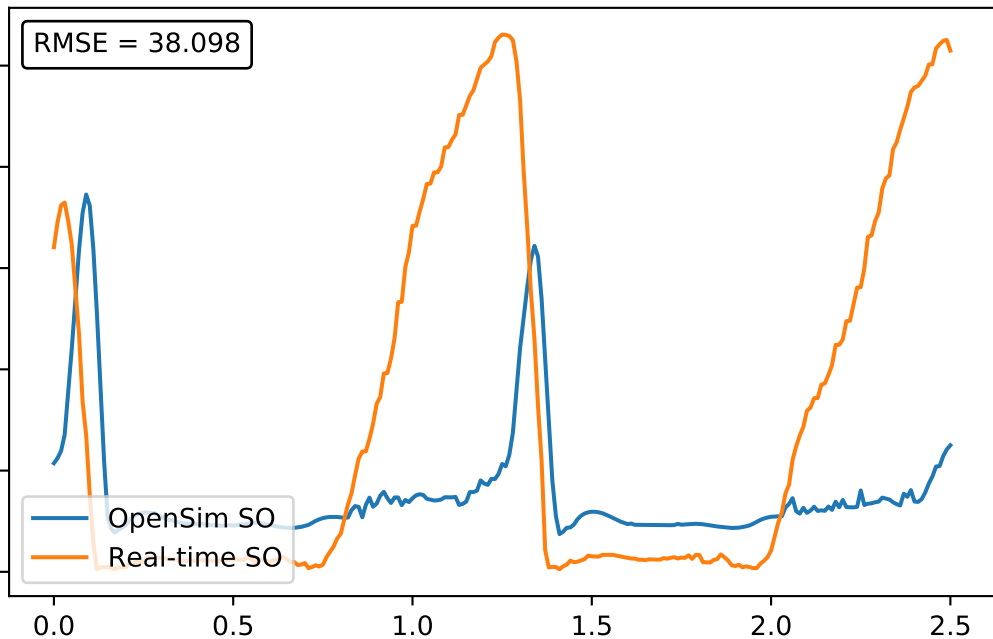
per\_long\_r

RMSE = 38.098

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time





per\_tert\_r

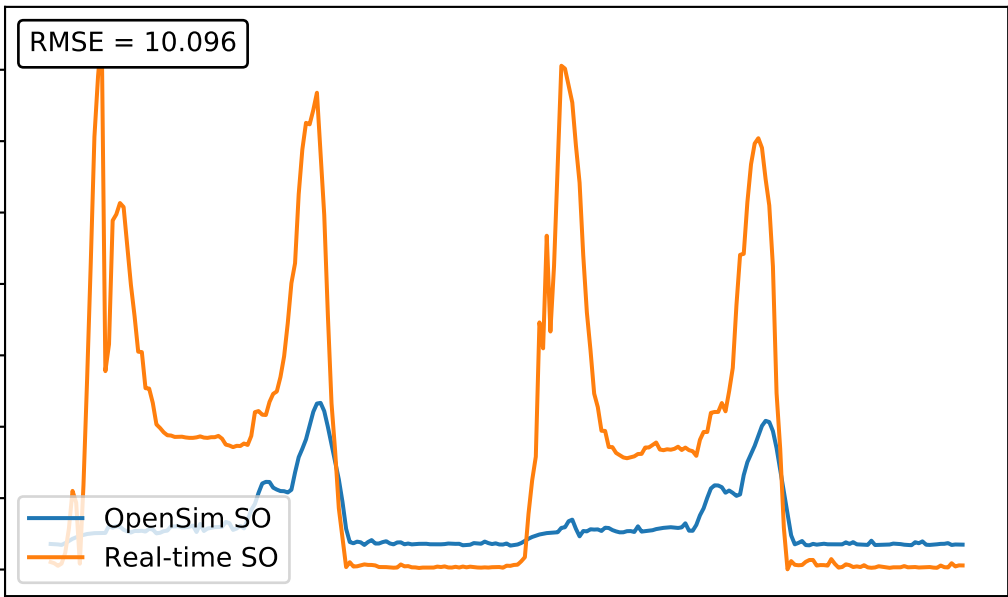
RMSE = 10.096

actuator forces (Nm | N)

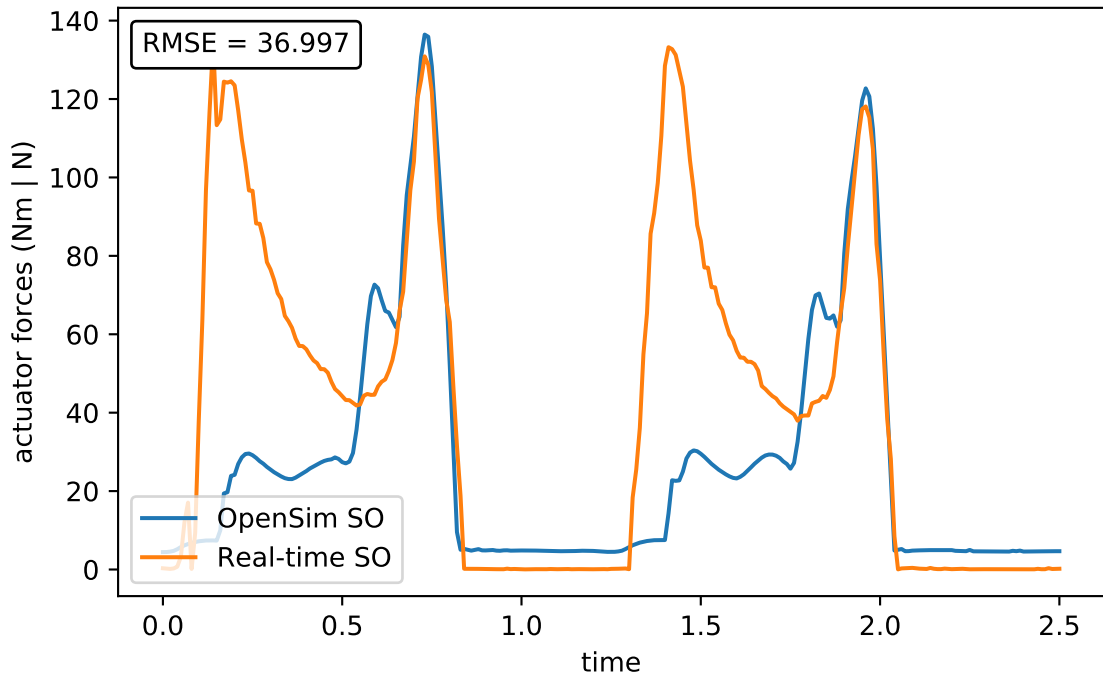
OpenSim SO  
Real-time SO

time

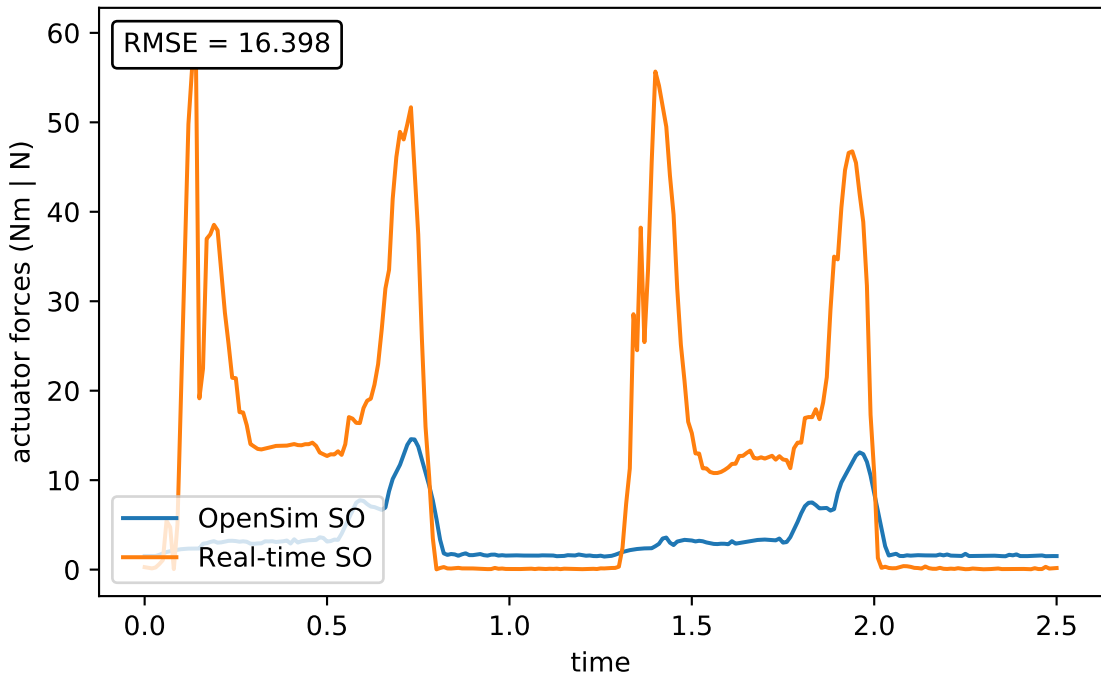
0.0 0.5 1.0 1.5 2.0 2.5



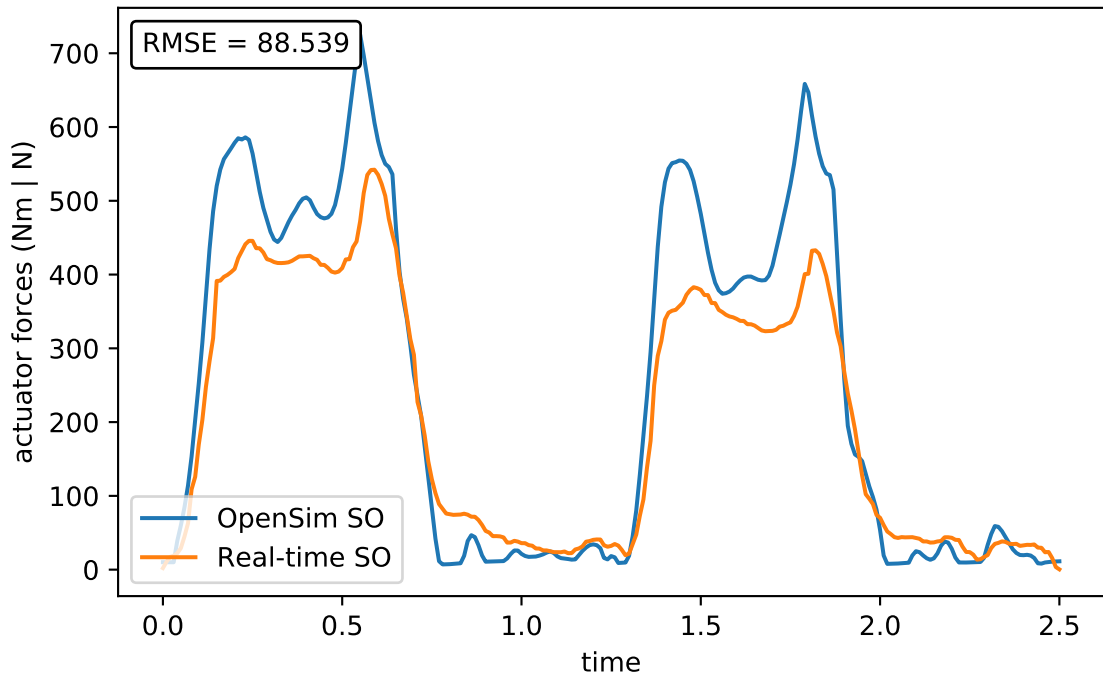
# ext\_dig\_r



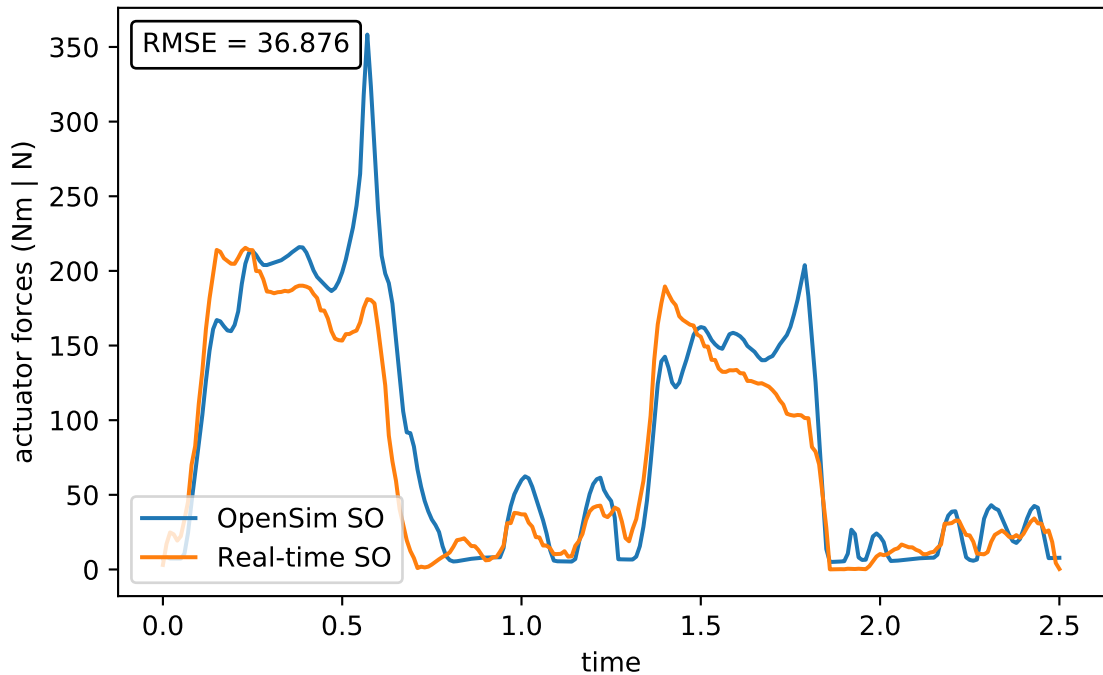
ext\_hal\_r



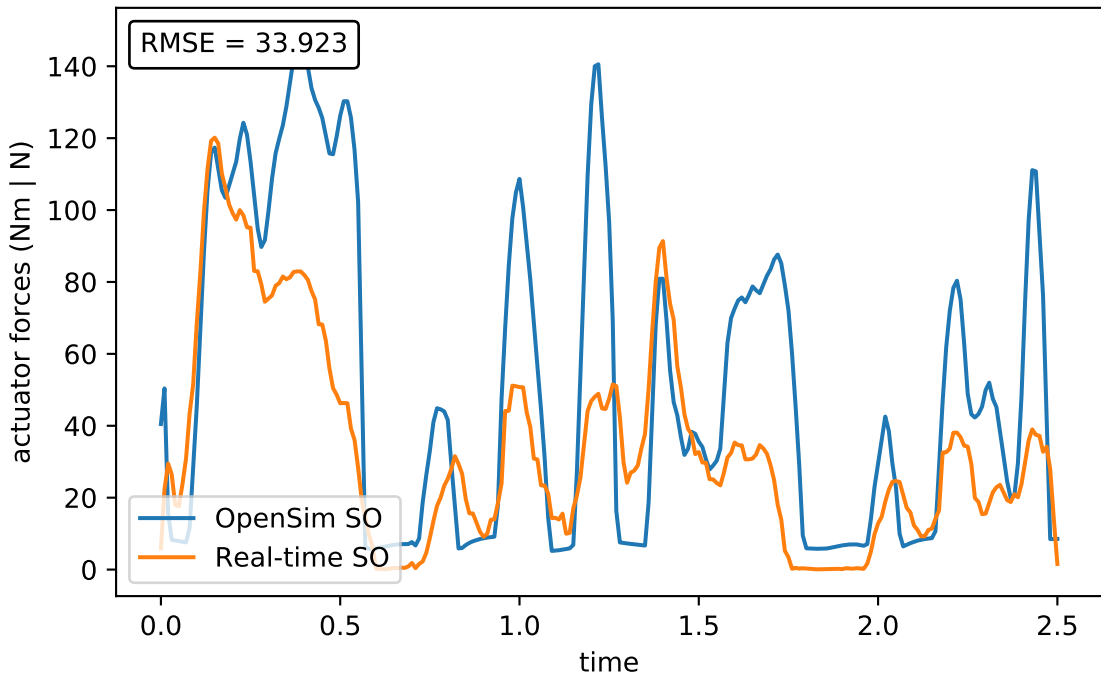
# glut\_med1\_l



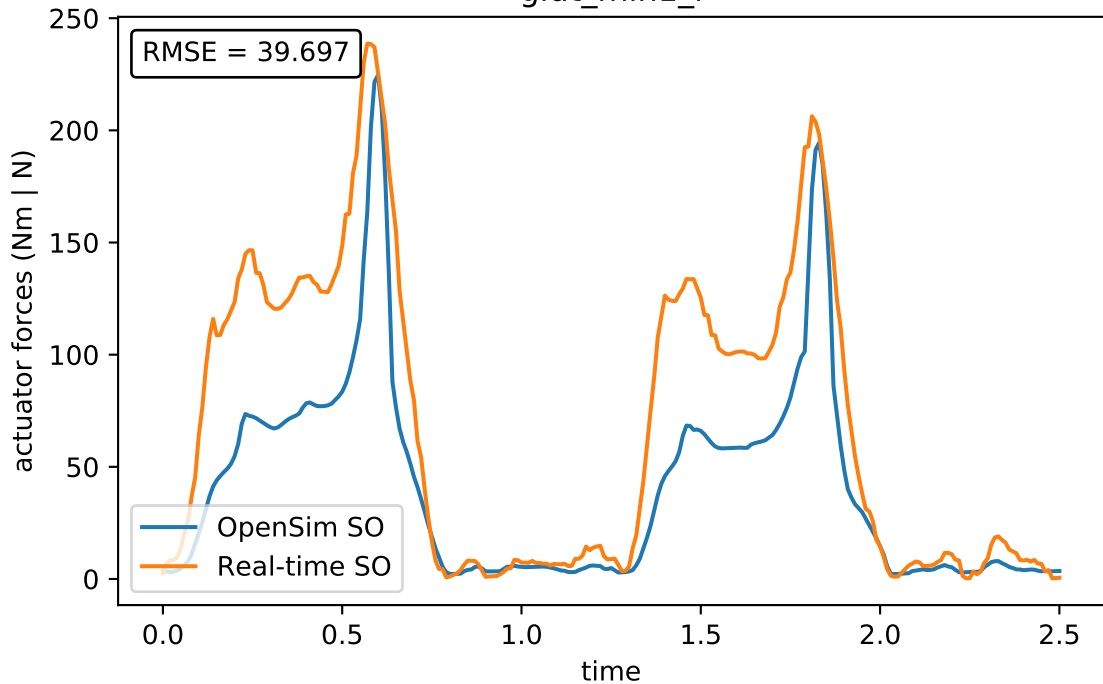
# glut\_med2\_l



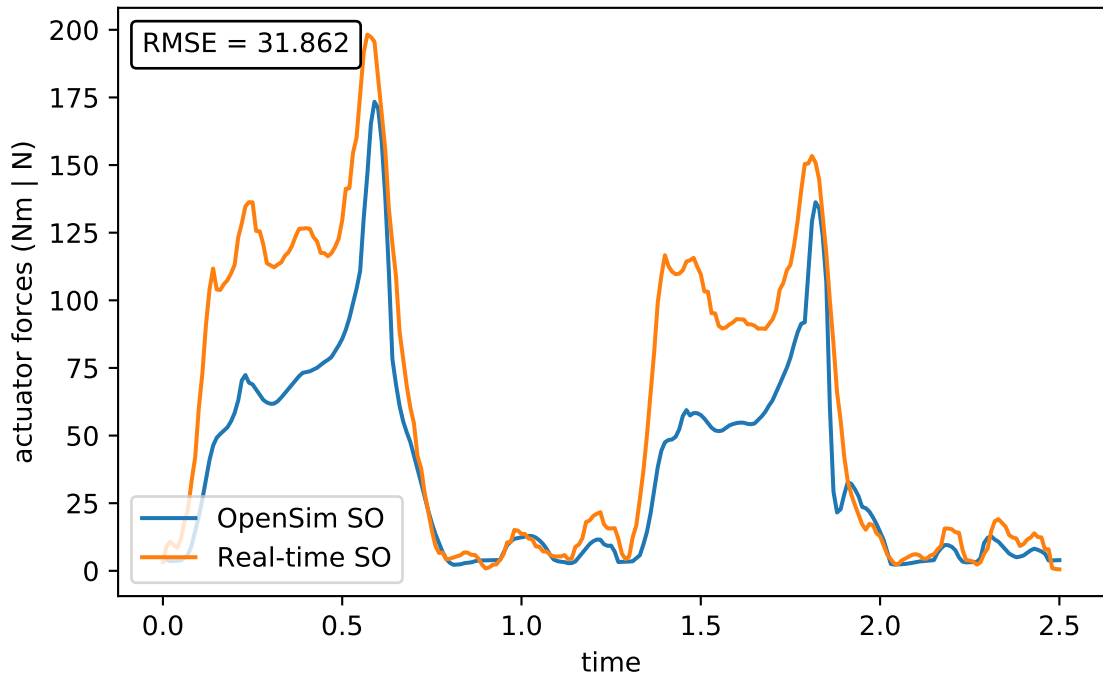
# glut\_med3\_l



# glut\_min1\_l

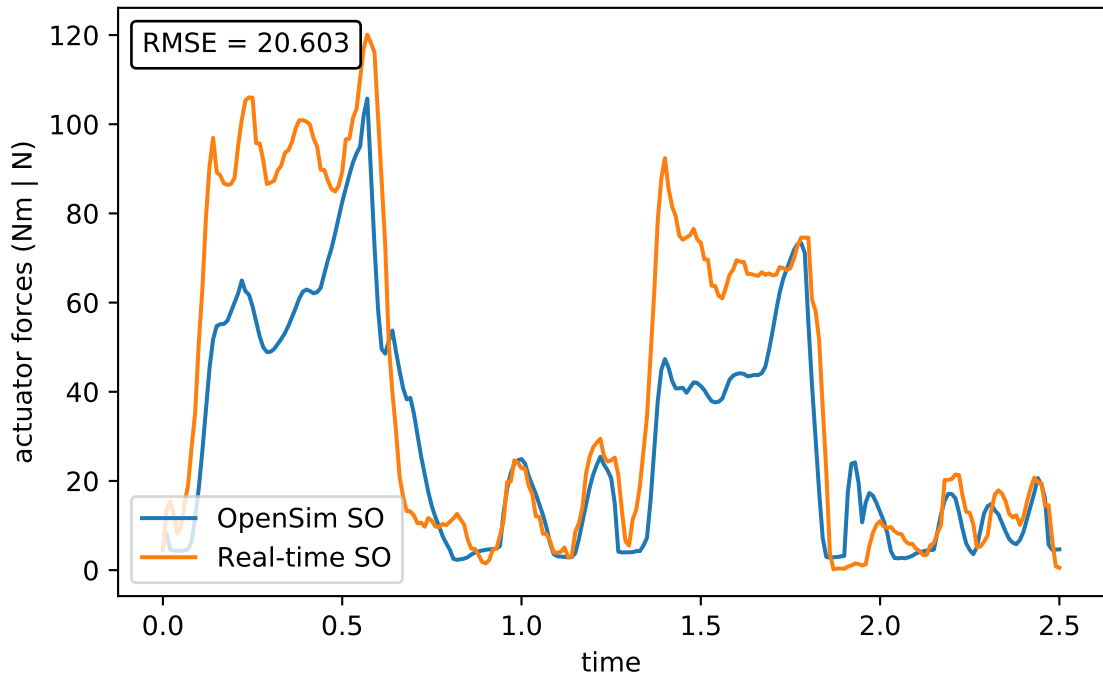


# glut\_min2\_l





# glut\_min3\_l



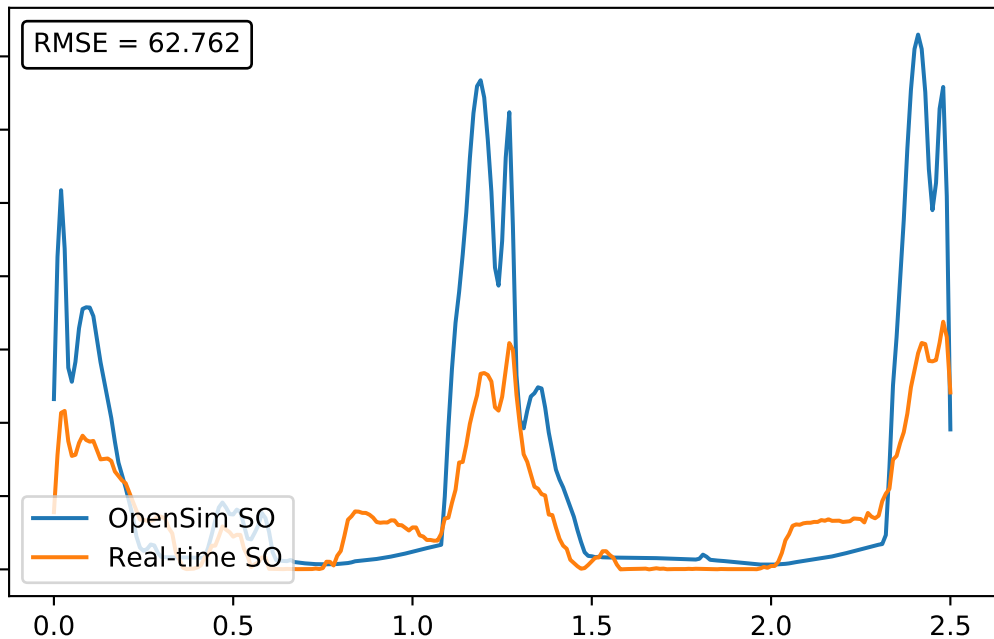
# semimem\_l

RMSE = 62.762

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



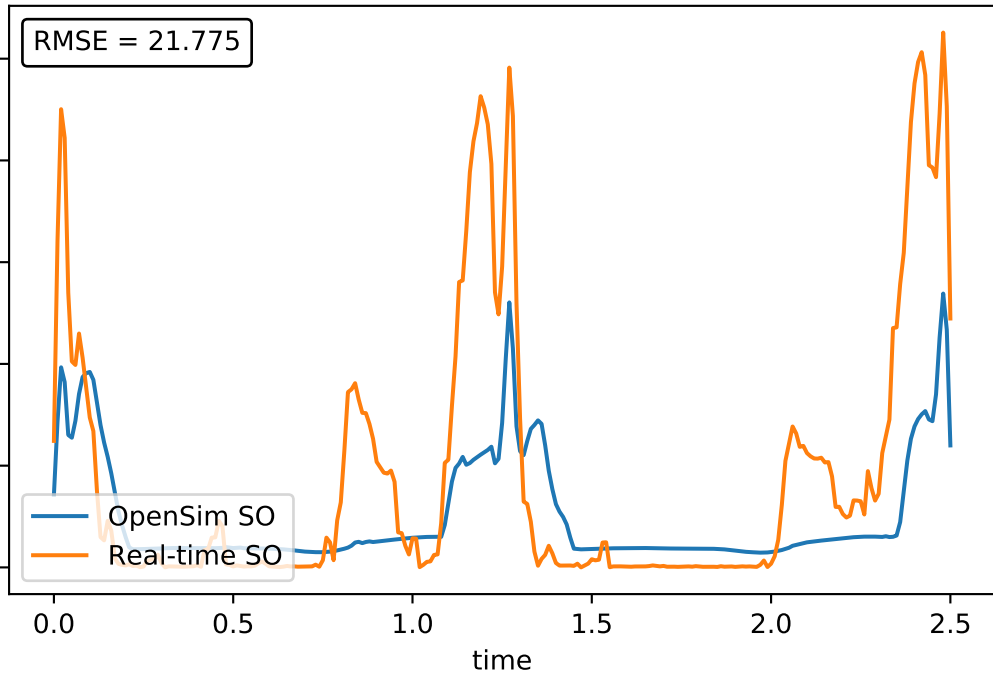
# semiten\_l

RMSE = 21.775

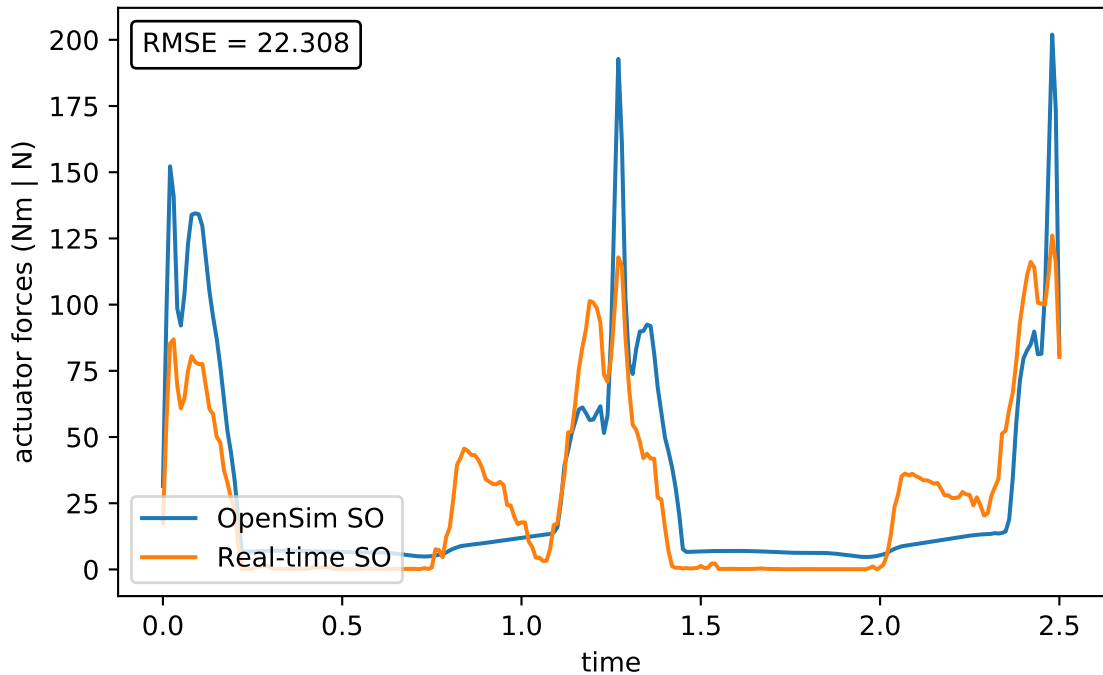
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

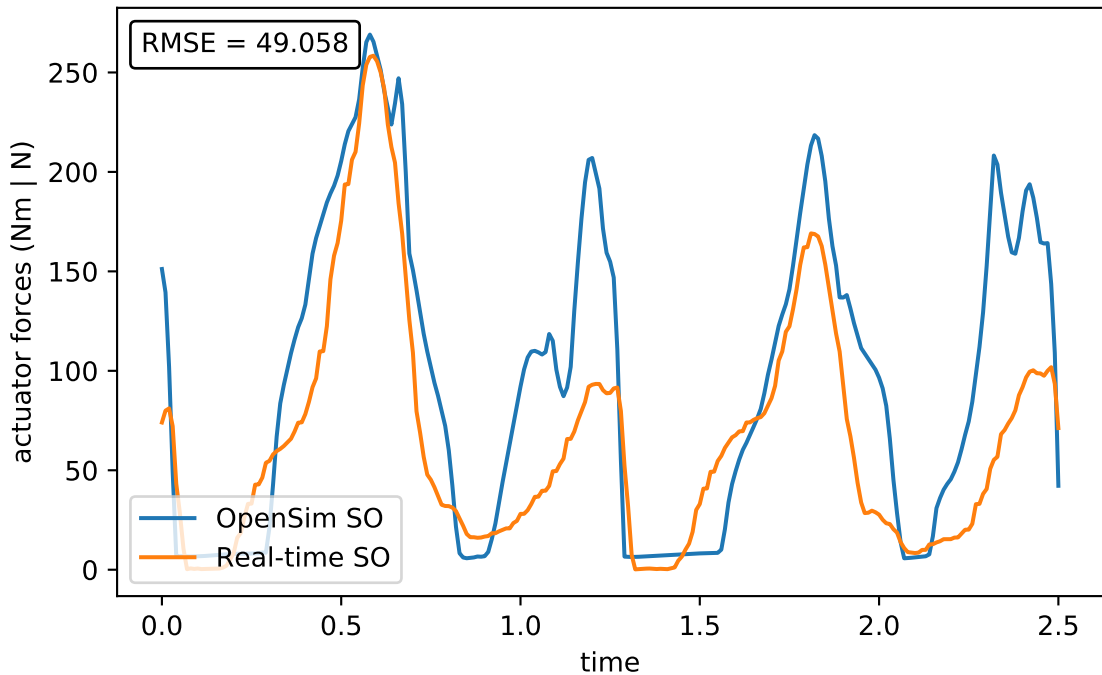
time



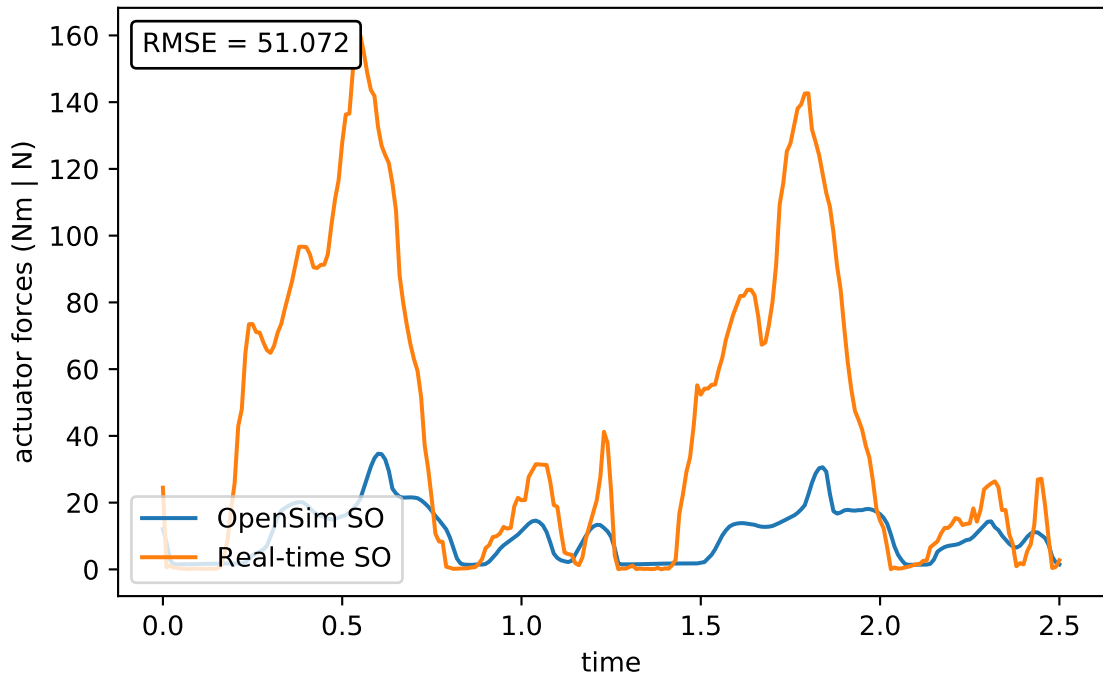
# bifemlh\_l



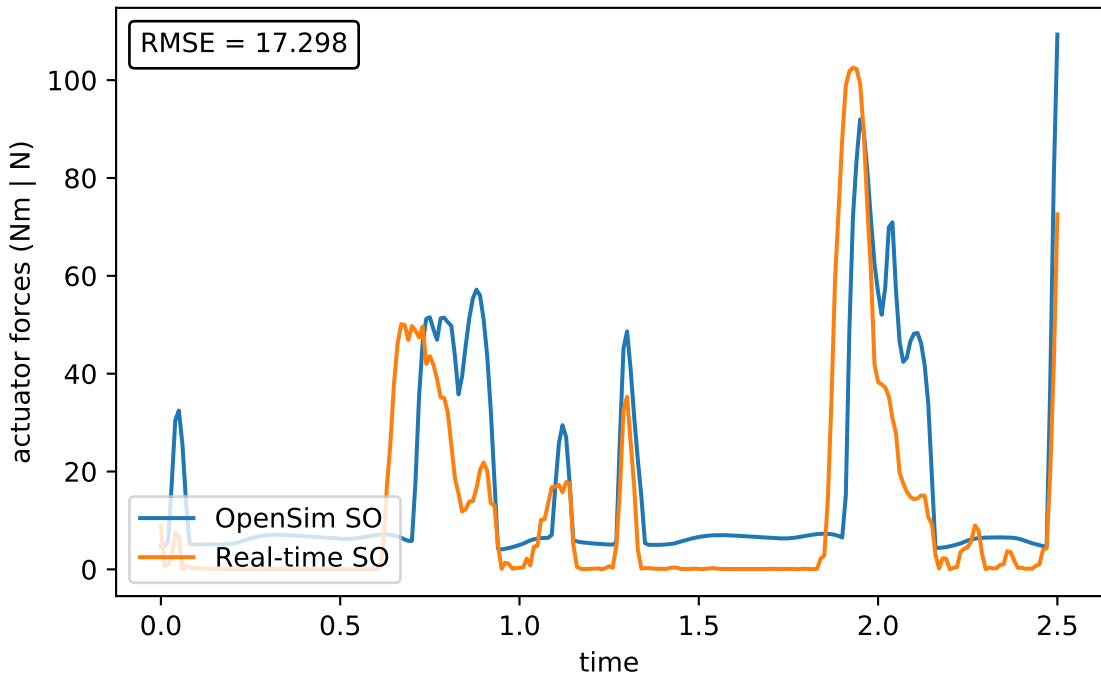
# bifemsh\_l



sar\_l



## add\_long\_l



add\_brev\_l

RMSE = 5.771

actuator forces (Nm | N)

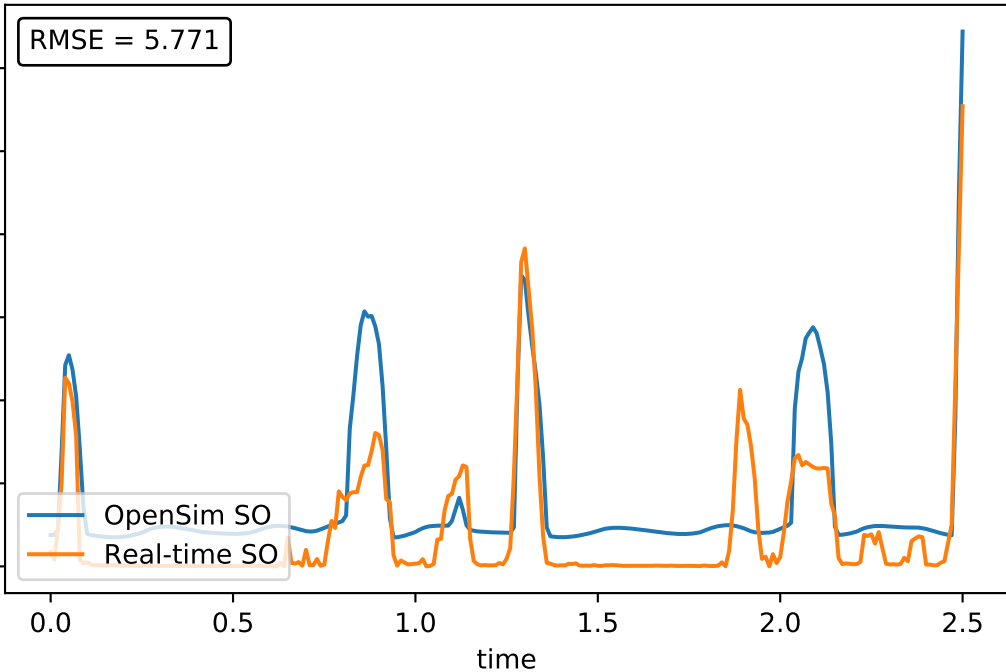
OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

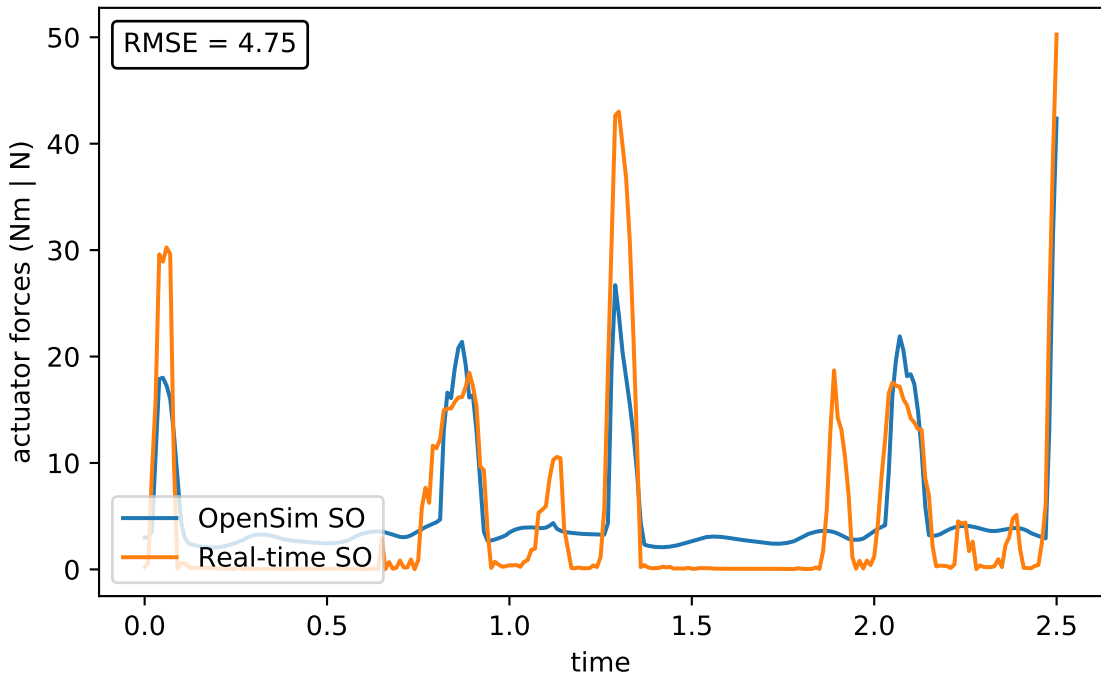
60  
50  
40  
30  
20  
10  
0

0.0 0.5 1.0 1.5 2.0 2.5

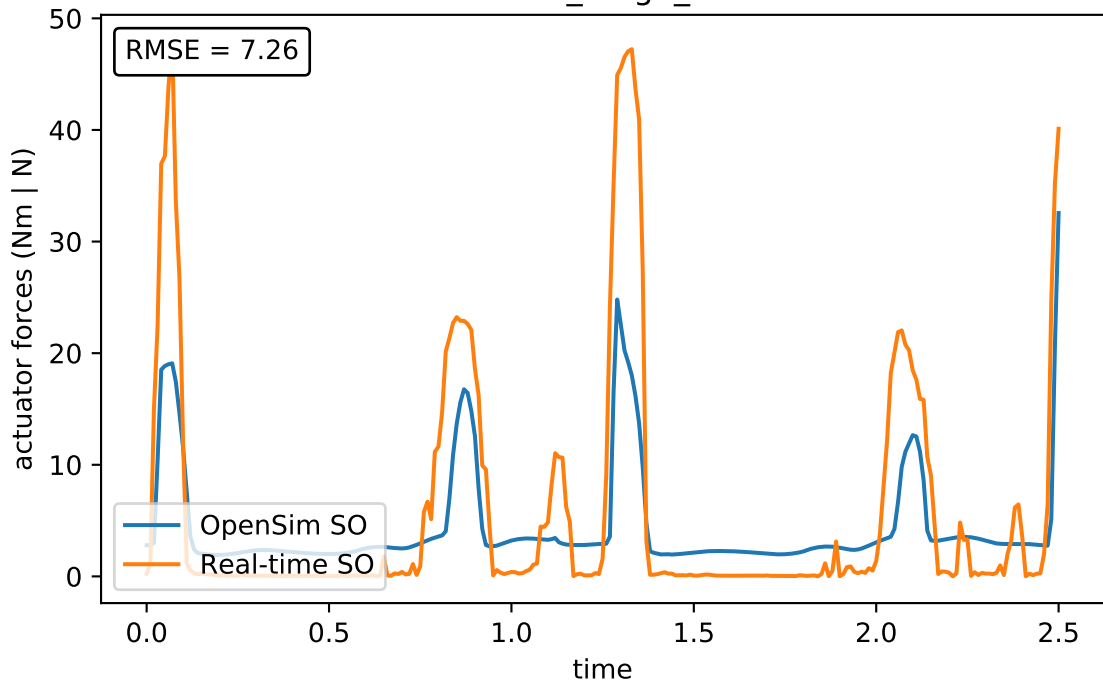




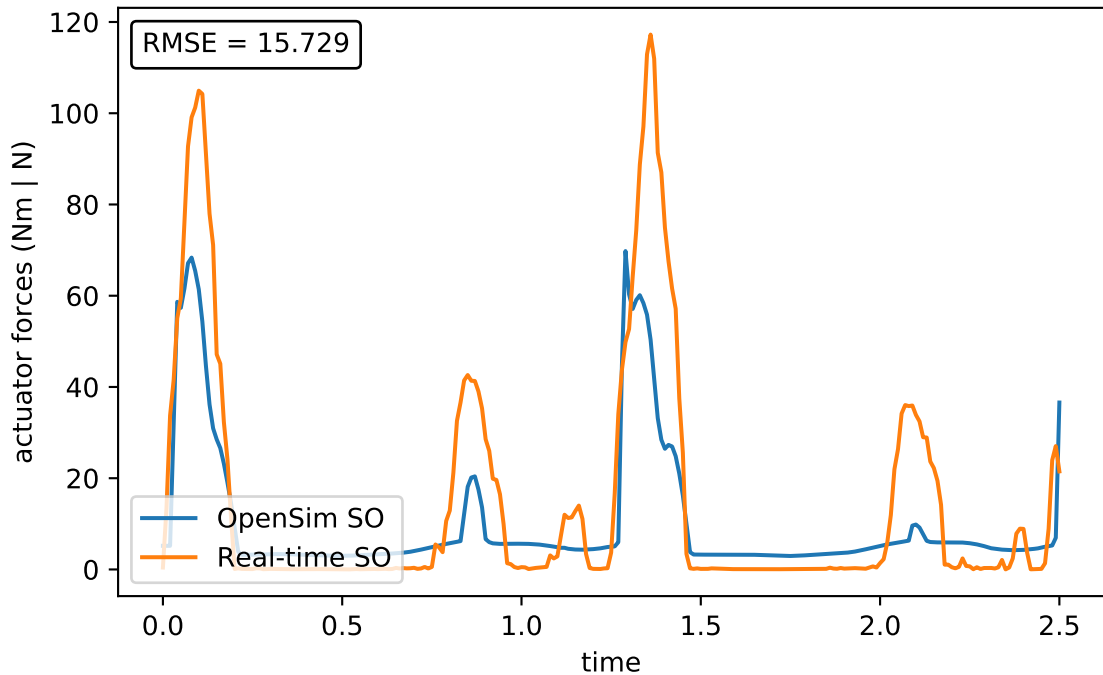
## add\_mag1\_l



## add\_mag2\_l



# add\_mag3\_l



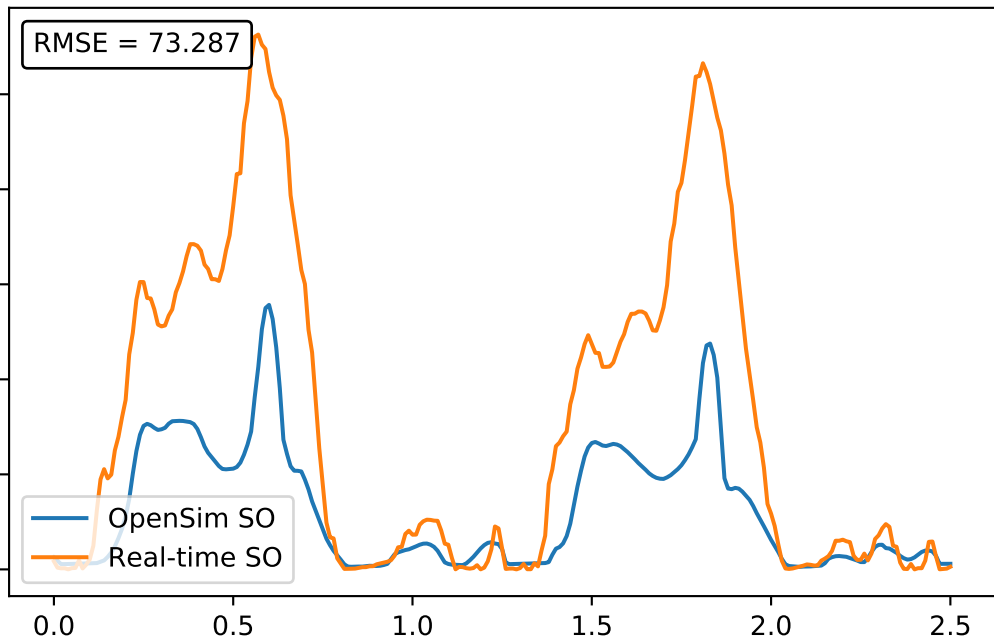
tfl\_l

RMSE = 73.287

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



pect\_l

RMSE = 8.889

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0

0.5

1.0

1.5

2.0

2.5

50

40

30

20

10

0

# grac\_l

RMSE = 6.515

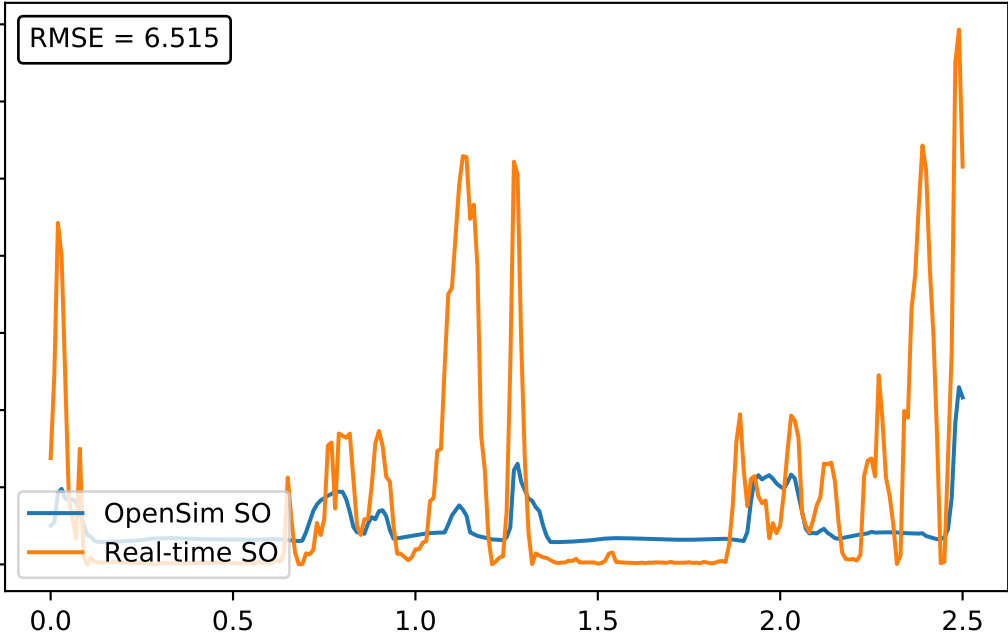
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

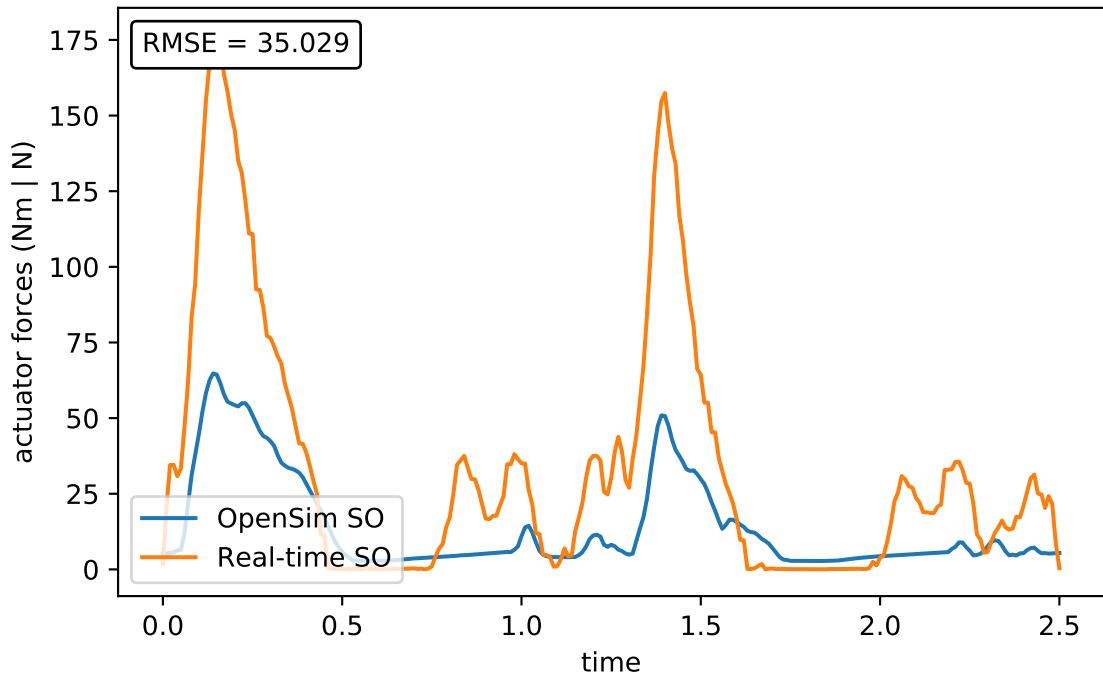
time

0.0 0.5 1.0 1.5 2.0 2.5

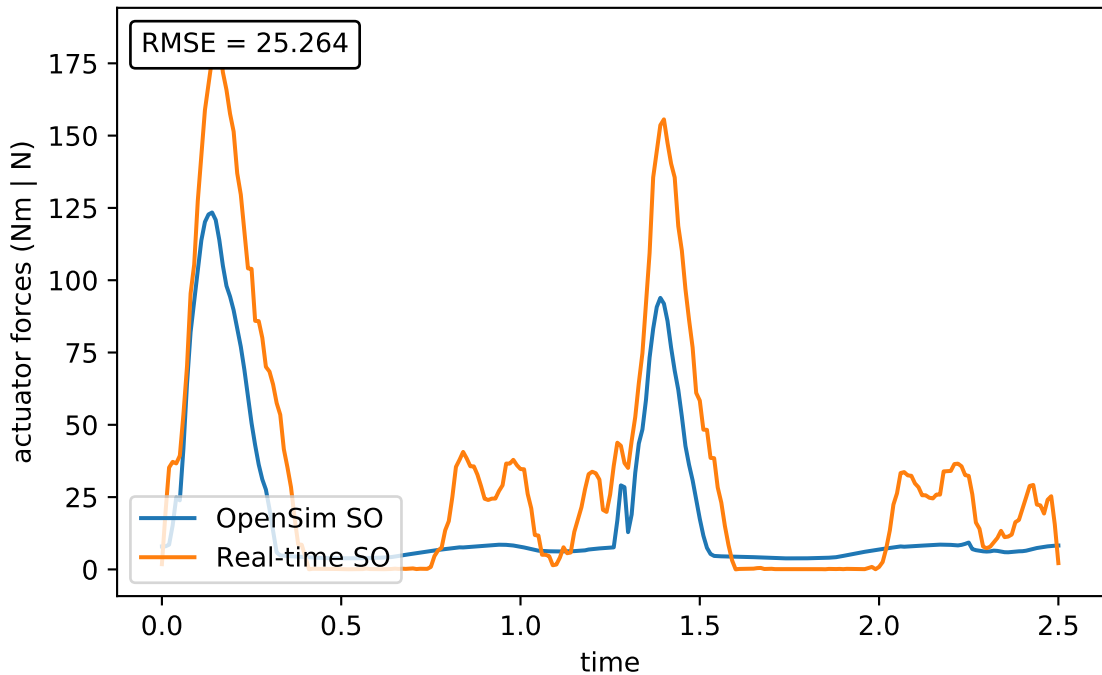
35  
30  
25  
20  
15  
10  
5  
0



# glut\_max1\_l

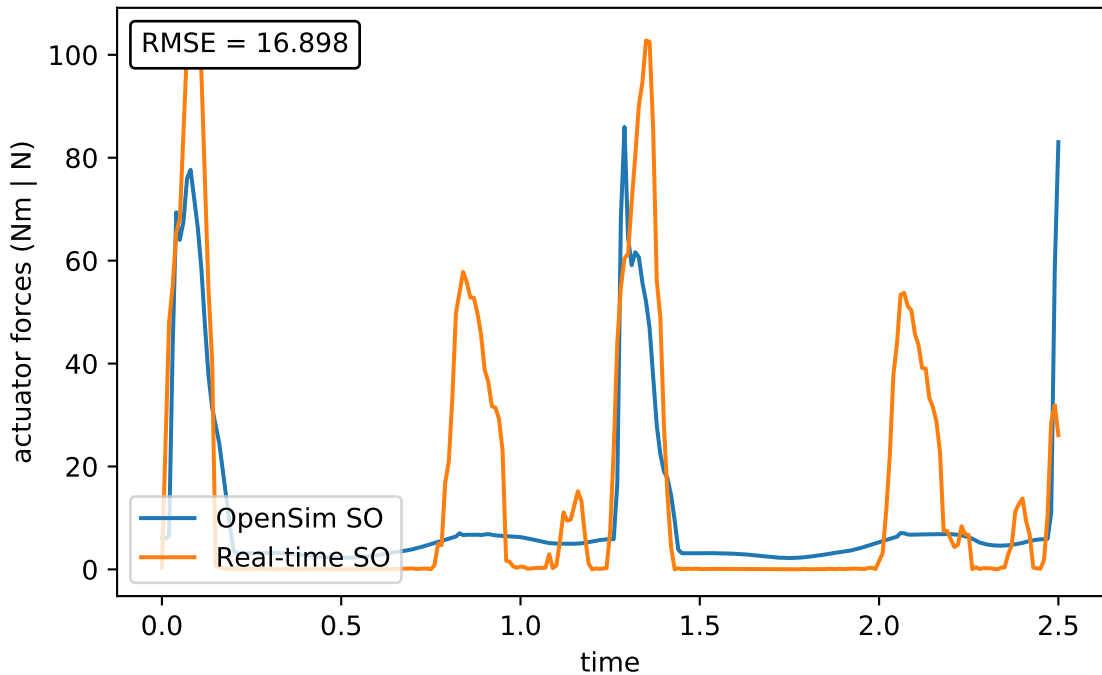


# glut\_max2\_l

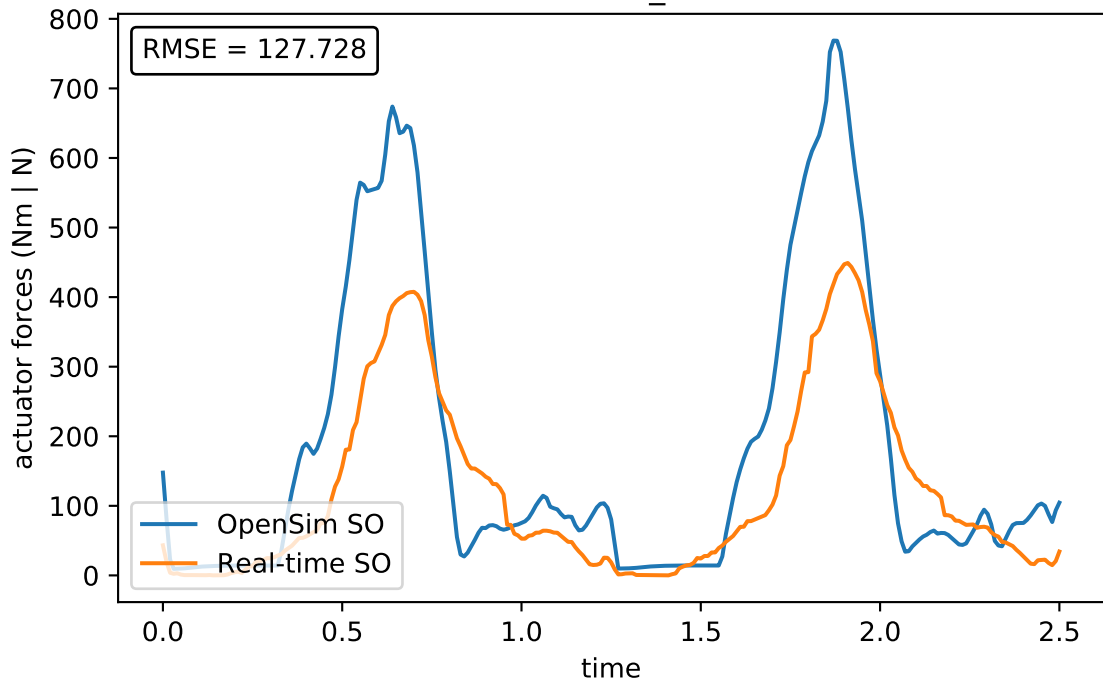




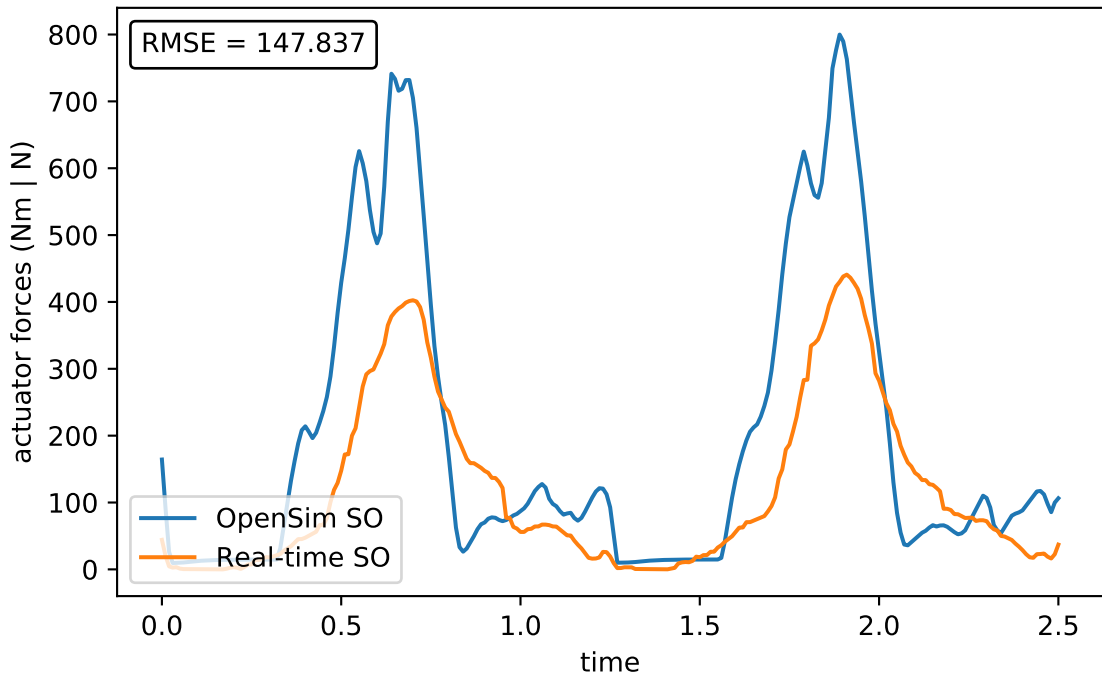
# glut\_max3\_l



# iliacus\_l



# psoas\_l



# quad\_fem\_l

RMSE = 6.396

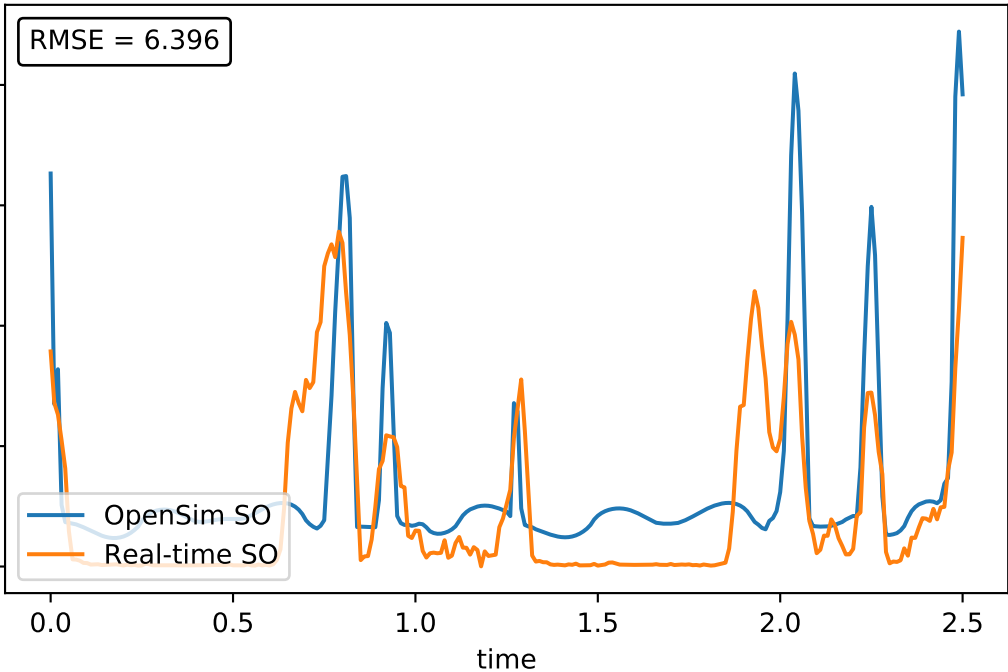
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

40  
30  
20  
10  
0



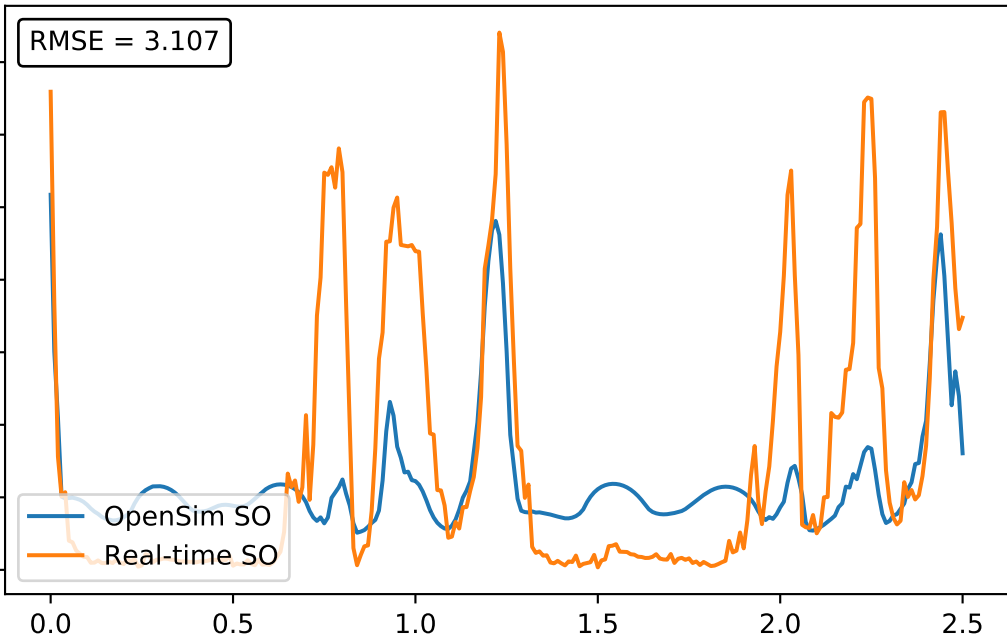
gem\_l

RMSE = 3.107

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



peri\_l

RMSE = 12.967

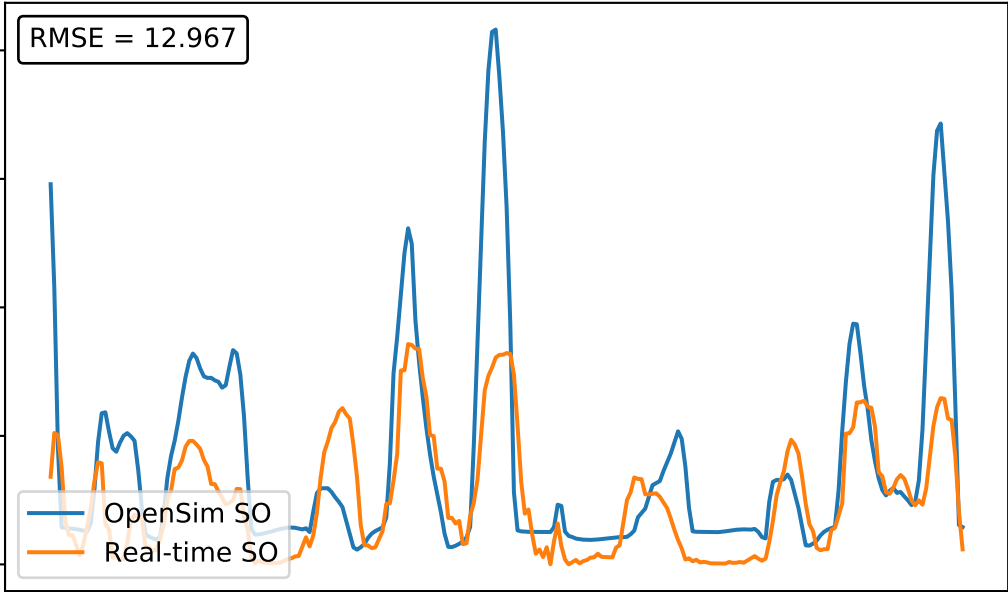
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

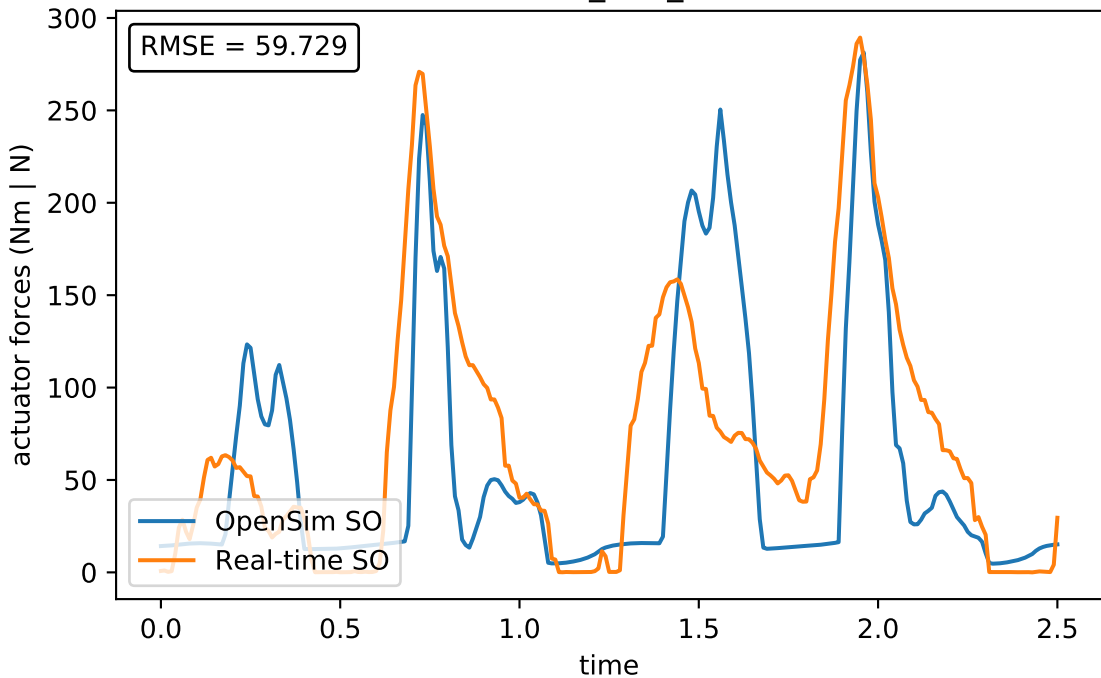
time

0.0 0.5 1.0 1.5 2.0 2.5

80  
60  
40  
20  
0



# rect\_fem\_l



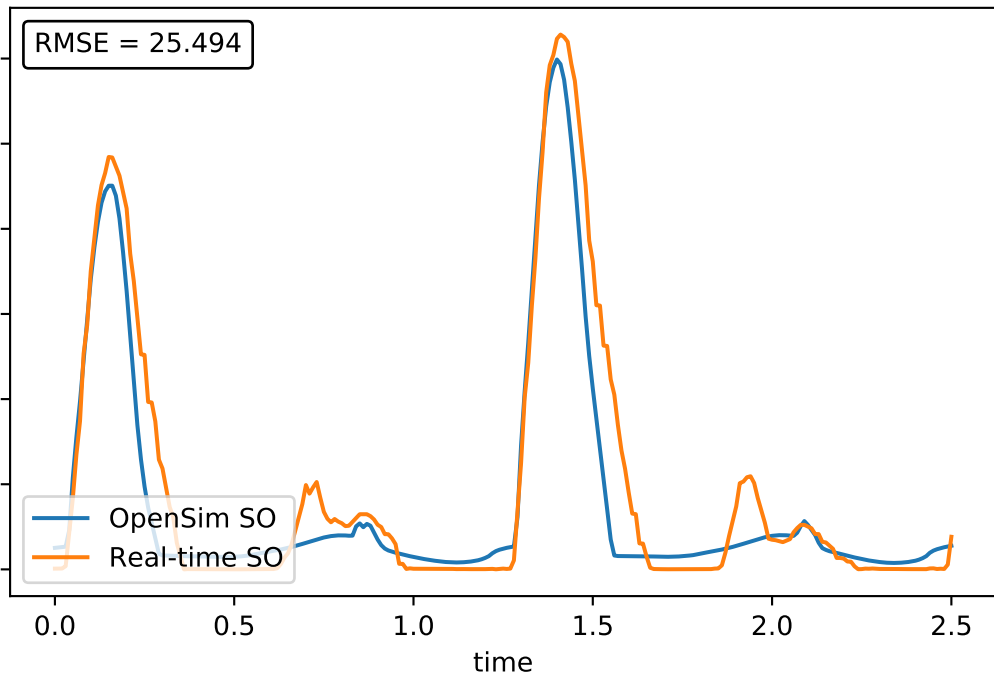
# vas\_med\_l

RMSE = 25.494

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time





vas\_int\_l

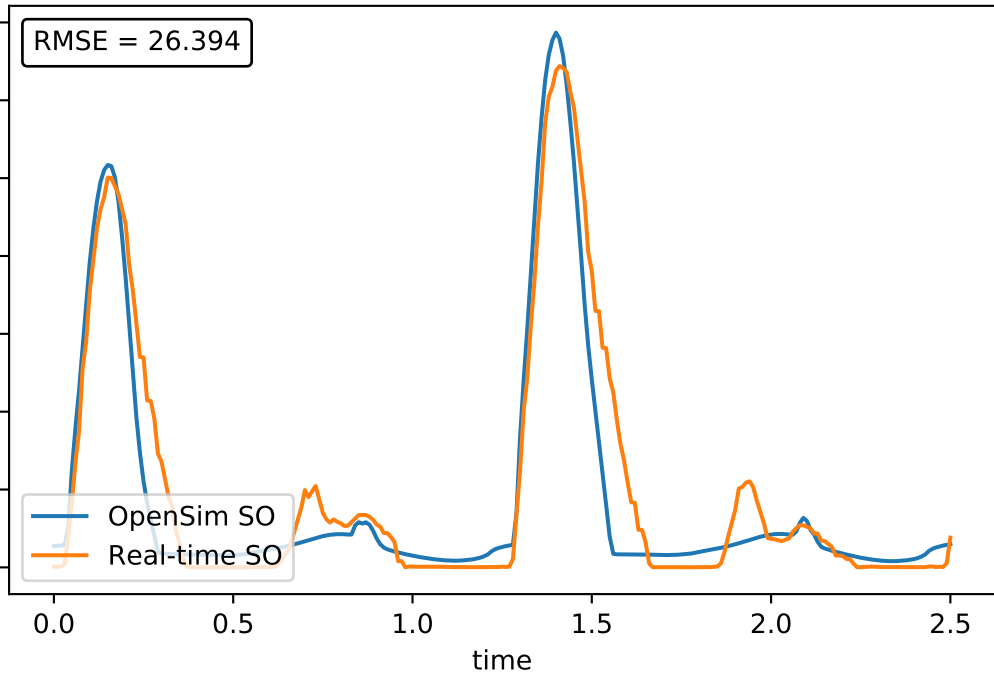
RMSE = 26.394

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5



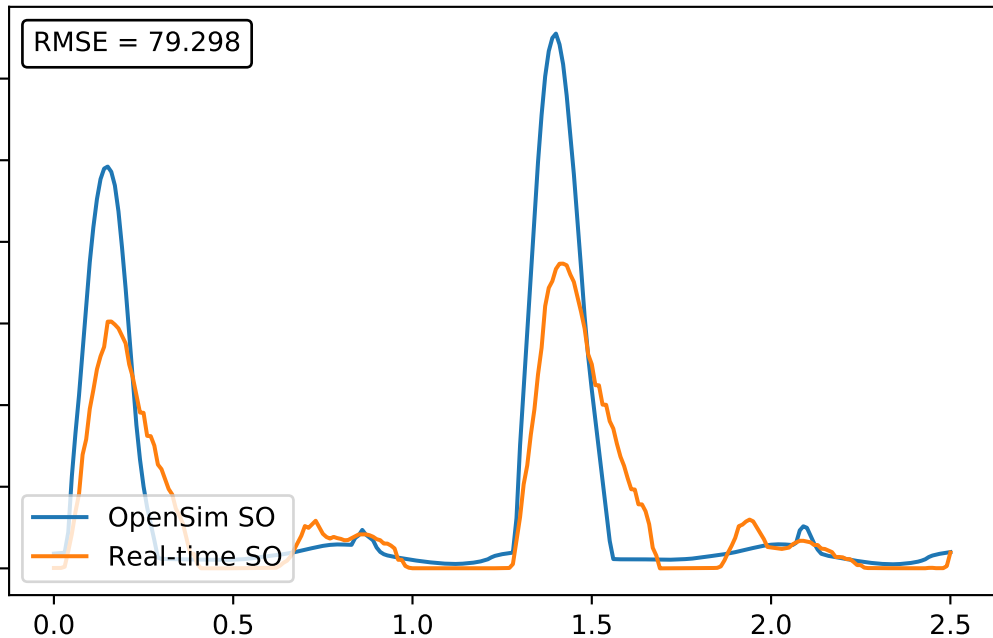
vas\_lat\_l

RMSE = 79.298

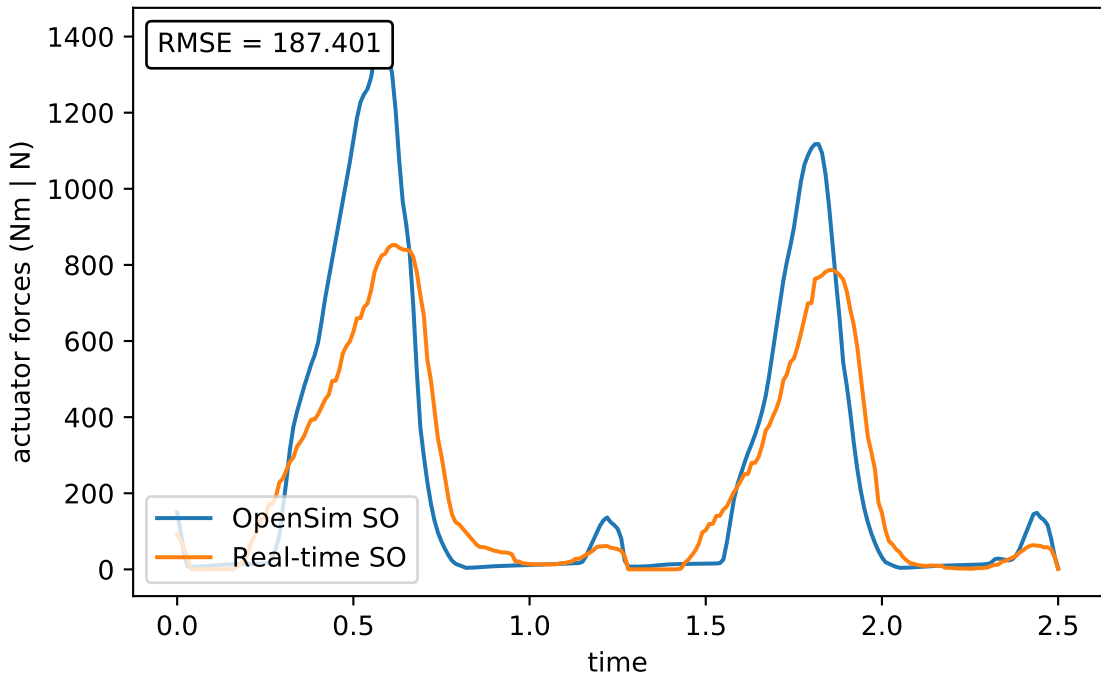
actuator forces (Nm | N)

— OpenSim SO  
— Real-time SO

time



med\_gas\_l



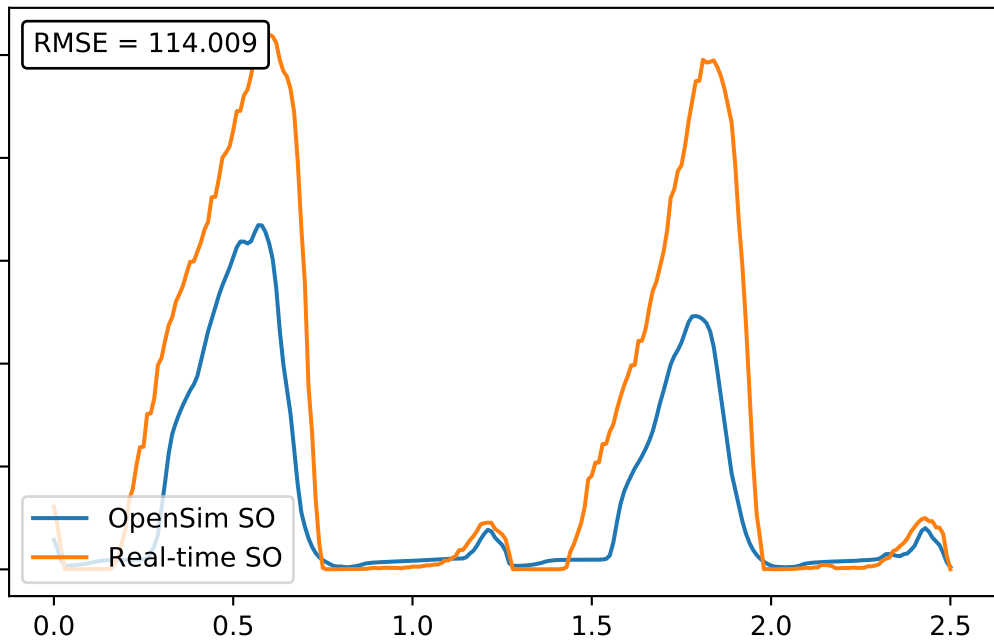
lat\_gas\_l

RMSE = 114.009

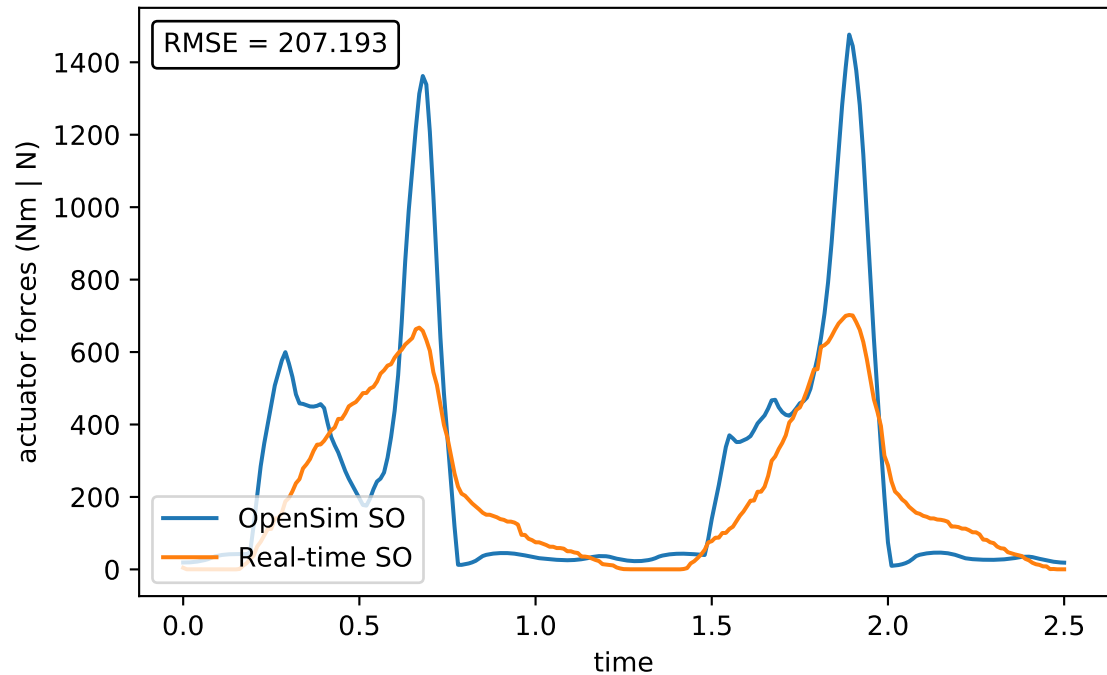
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

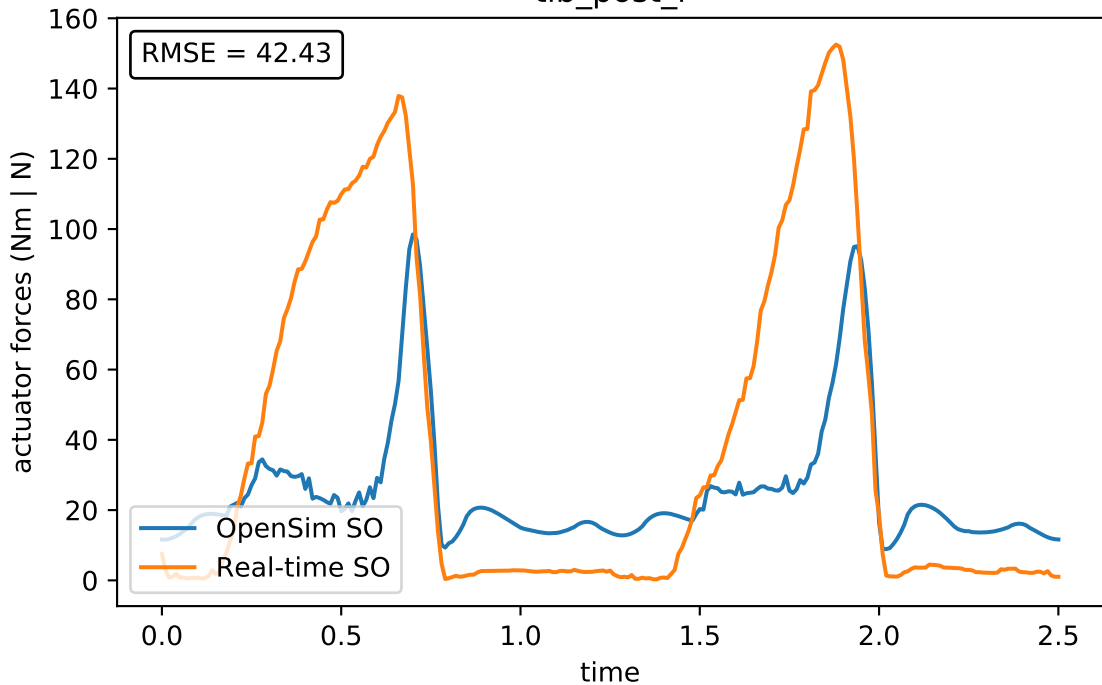
time



# soleus\_l



# tib\_post\_l



# flex\_dig\_l

RMSE = 16.744

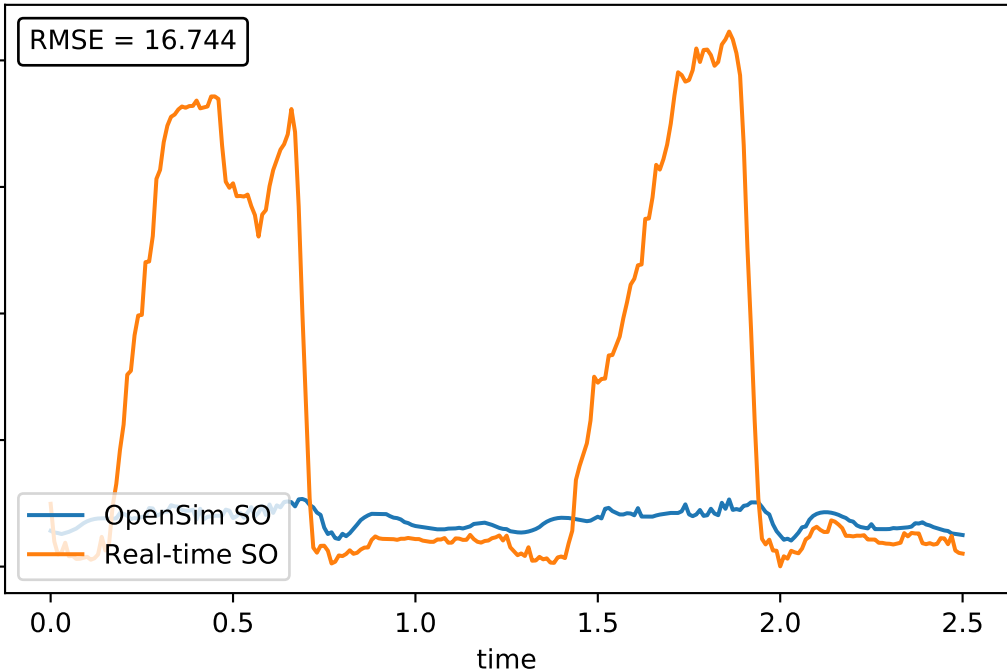
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

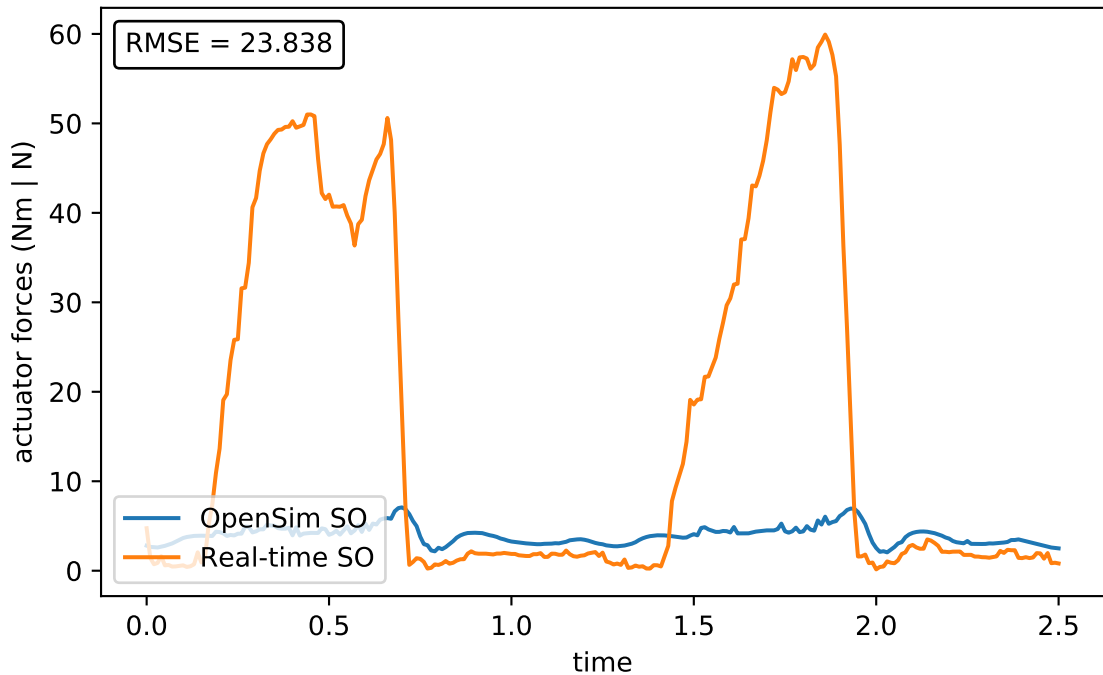
time

0.0 0.5 1.0 1.5 2.0 2.5

40  
30  
20  
10  
0



# flex\_hal\_l





tib\_ant\_l

RMSE = 102.462

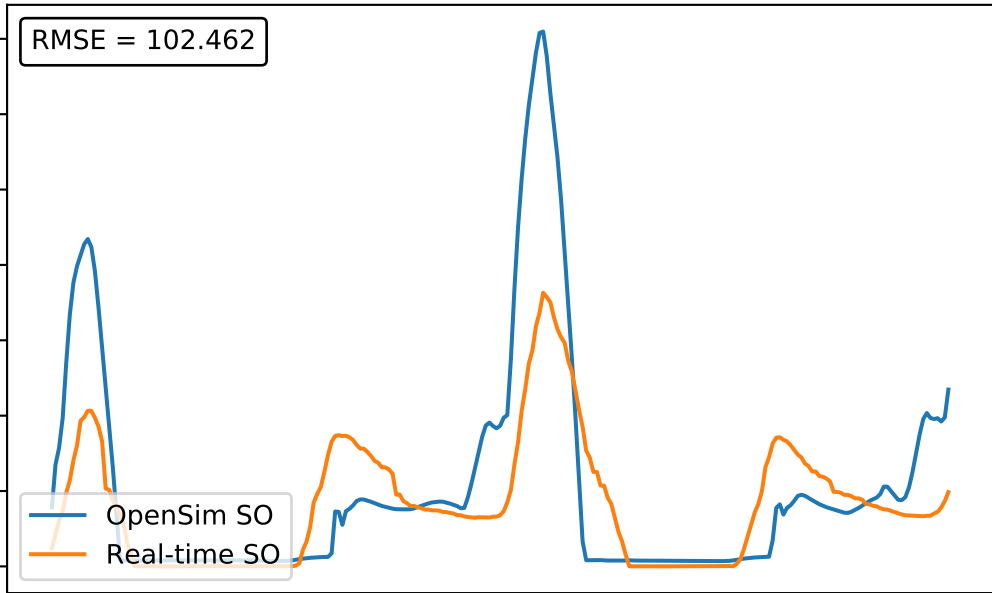
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

700  
600  
500  
400  
300  
200  
100  
0



per\_brev\_l

RMSE = 10.995

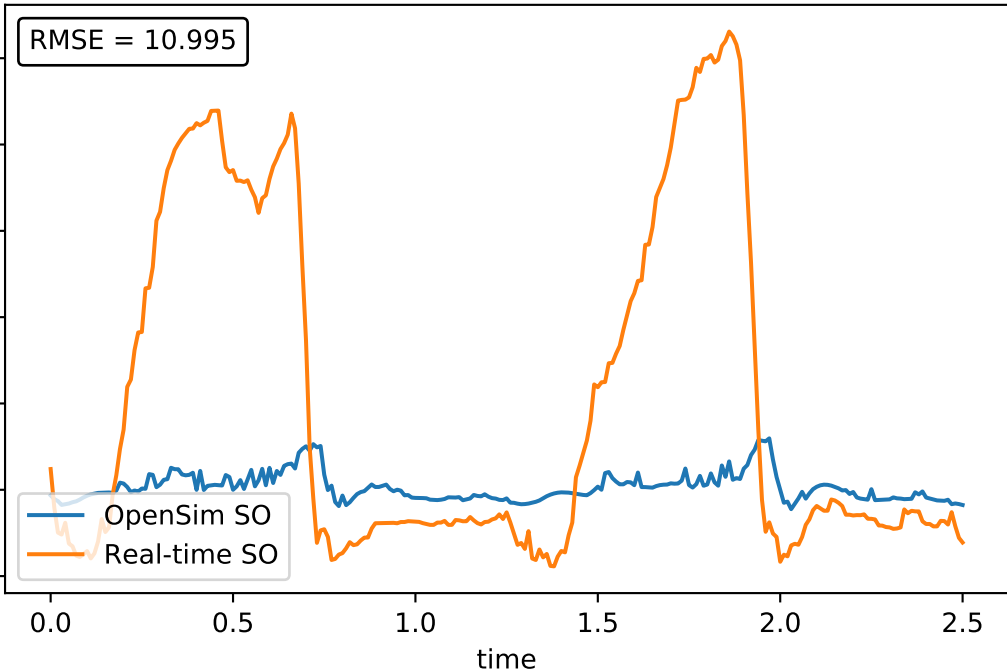
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

30  
25  
20  
15  
10  
5  
0



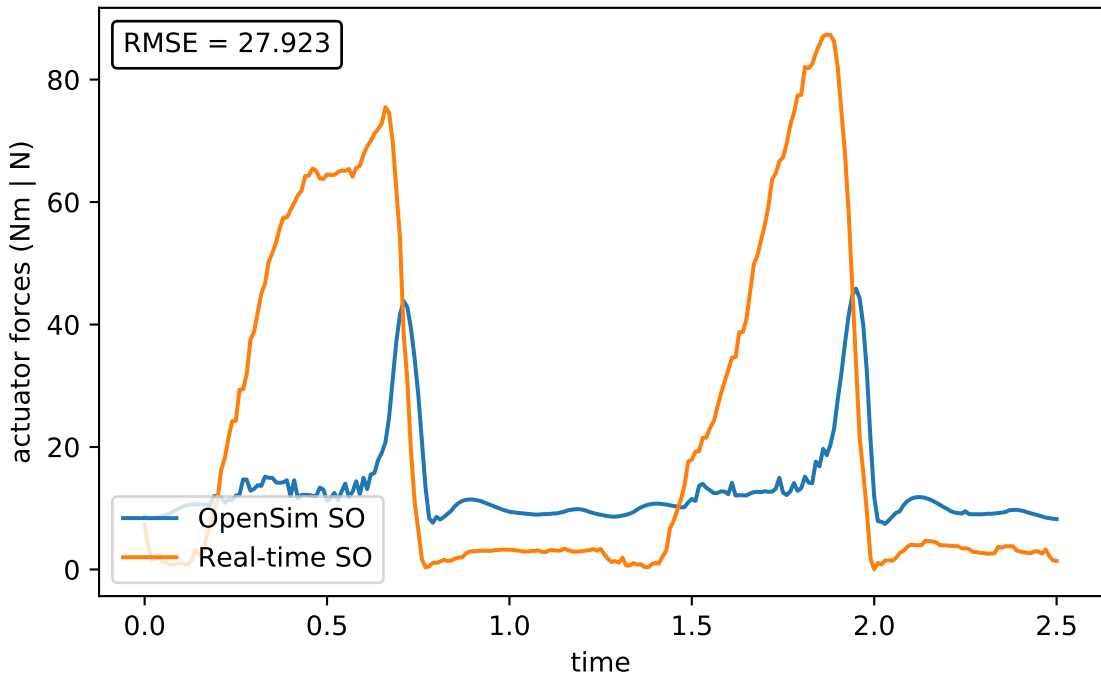
per\_long\_l

RMSE = 27.923

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



per\_tert\_l

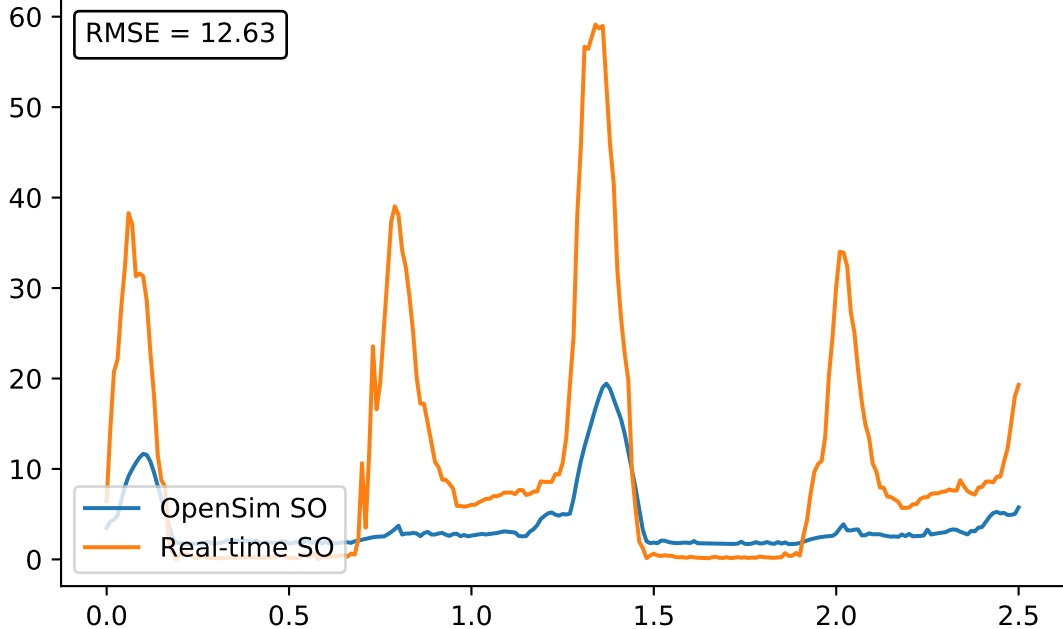
RMSE = 12.63

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5



ext\_dig\_l

RMSE = 33.918

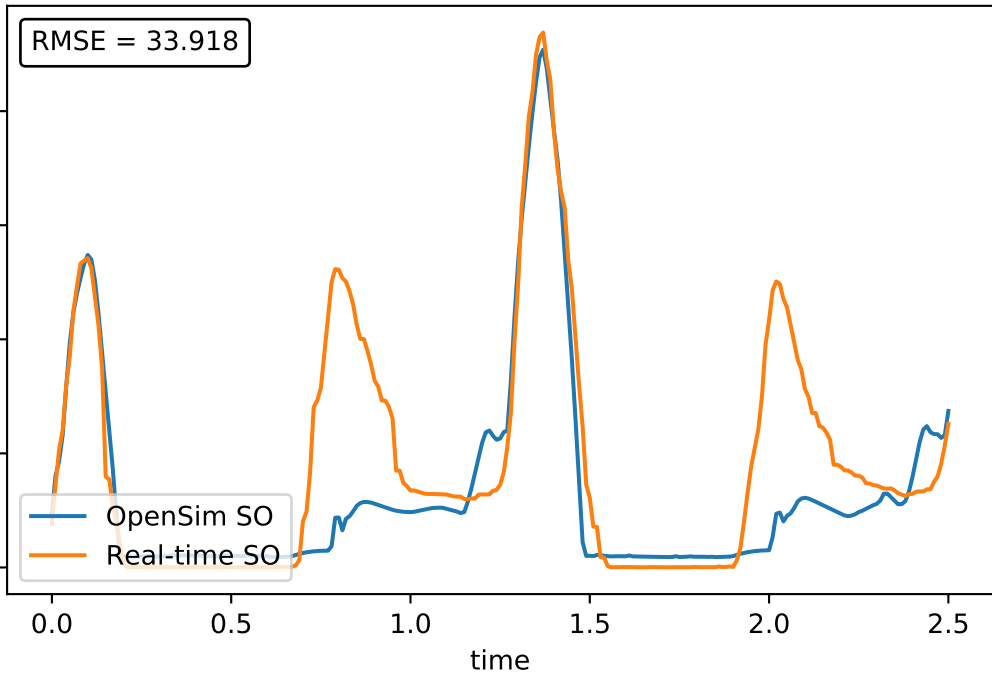
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

200  
150  
100  
50  
0



ext\_hal\_l

RMSE = 20.54

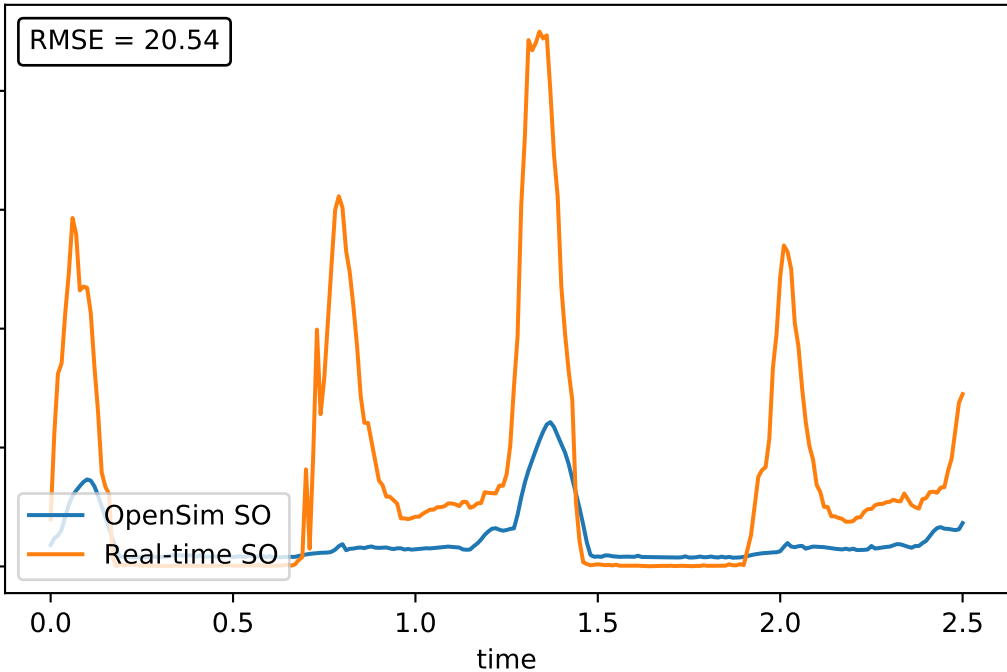
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

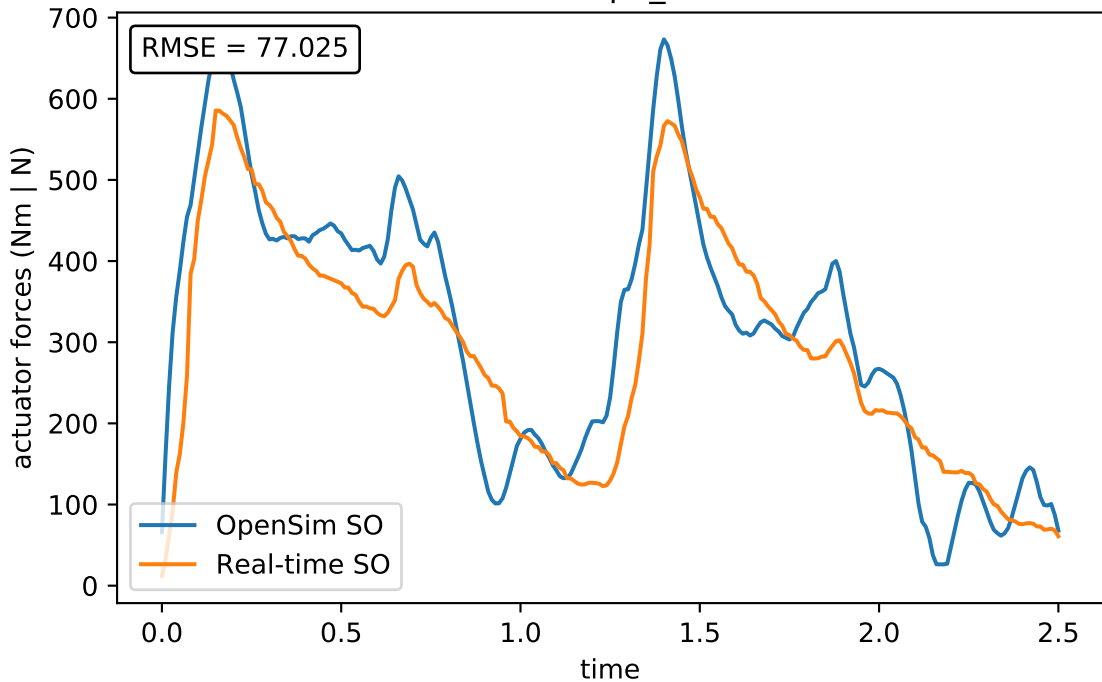
time

0.0 0.5 1.0 1.5 2.0 2.5

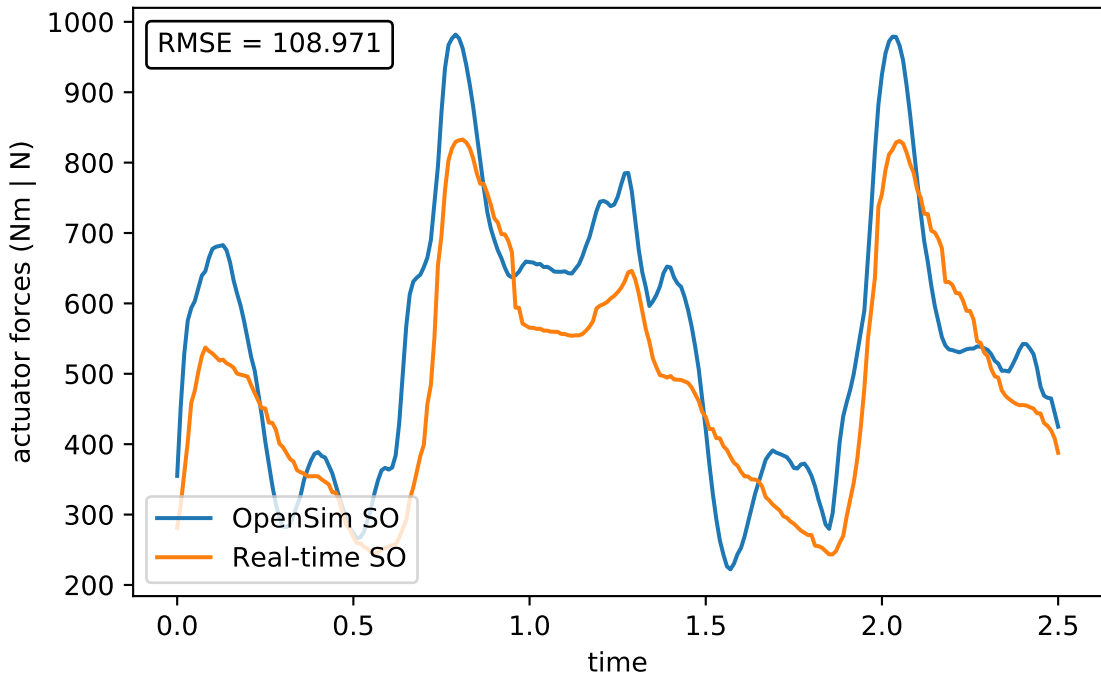
80  
60  
40  
20  
0



# ercspn\_r

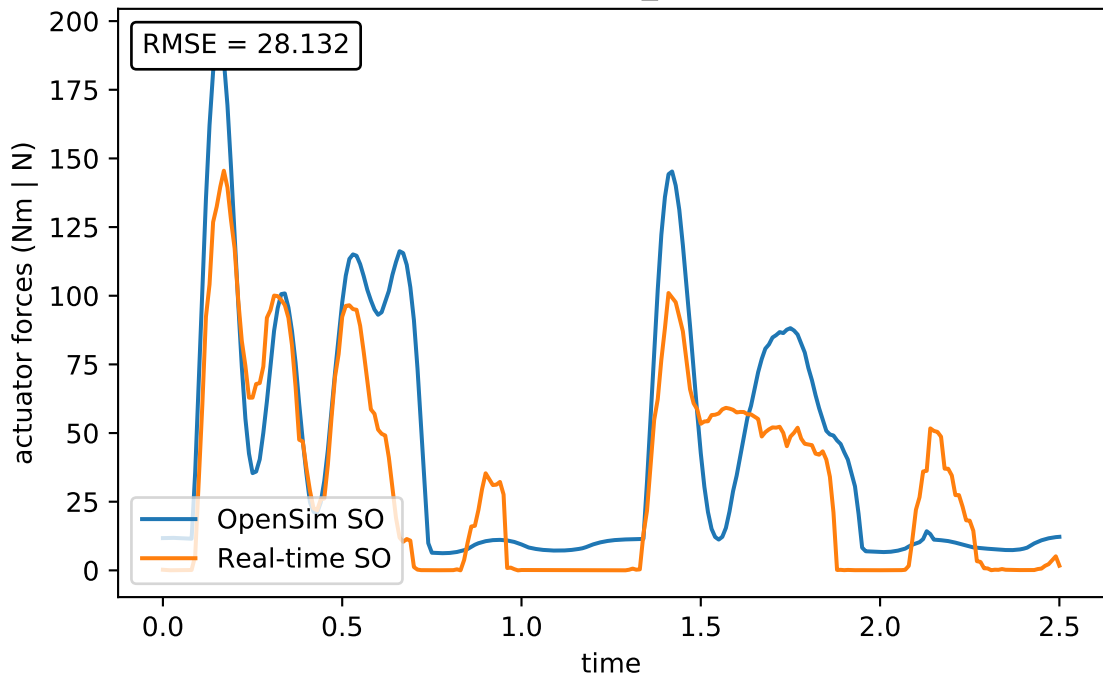


# ercspn\_l





intobl\_r



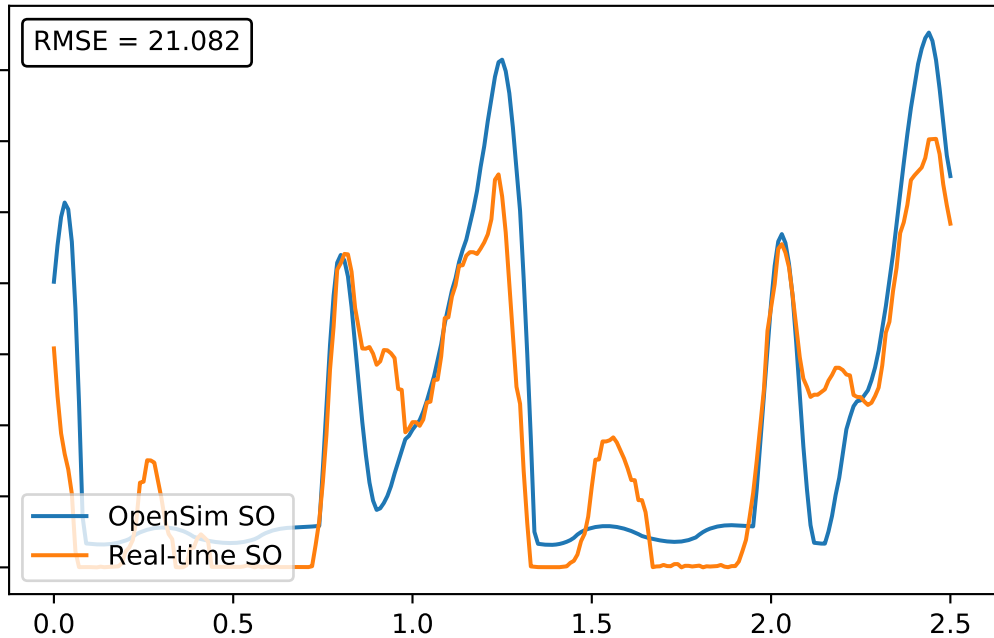
intobl\_l

RMSE = 21.082

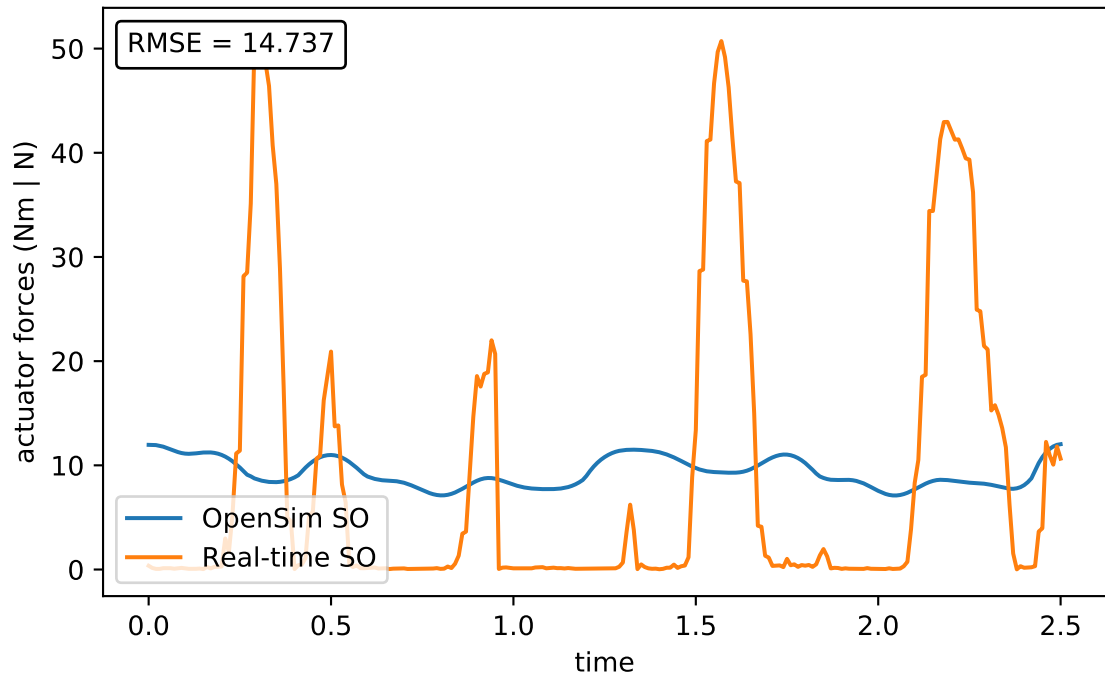
actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time



# extobl\_r



# extobl\_l

RMSE = 15.021

actuator forces (Nm | N)

OpenSim SO  
Real-time SO

time

0.0 0.5 1.0 1.5 2.0 2.5

50  
40  
30  
20  
10  
0

