Thesis Proposal v2

Aim 1 – Design and validate a many-muscles hindlimb model

* Muscle paths
* Muscle moment arms
* Muscle LT/ST Parameters
  + Lr/Lw from maxmin
  + STmax/steep/yoff from STsolver
* VE properties from hanging leg experiments/optimization

Aim 2 – Analyze the consequences of VE properties on motor control

* Decomposition of forces into activation
* Scaling the leg and testing

Aim 3 – Testing different control strategies for different VE configurations