

## $squats A sym1\_grf\_raw.mot$ ground\_force\_2\_mx ground\_force\_2\_my ground\_force\_2\_mz 0.05 0.05 1.0 torque (N-m) torque (N-m) torque (N-m) 0.5 0.00 0.00 0.0 -0.5 -0.05 -0.05 0.0 0.0 10.0 time (s) time (s) time (s) ground\_force\_3\_vx ground\_force\_3\_vy ground\_force\_3\_vz 0.05 0.05 0.05 force (N) force (N) force (N) 0.00 0.00 0.00 -0.05 <del>-</del>0.05 -0.05 0.0 5.0 10.0 0.0 5.0 10.0 0.0 5.0 10.0 time (s) time (s) time (s) ground\_force\_3\_px ground\_force\_3\_py ground\_force\_3\_pz 0.05 0.05 0.05 position (m) position (m) position (m) 0.00 0.00 0.00 -0.05 E -0.05 <u></u> -0.05 0.0 5.0 0.0 5.0 0.0 10.0 10.0 10.0 time (s) time (s) time (s) ground\_force\_3\_mx ground\_force\_3\_my ground\_force\_3\_mz 0.05 0.05 0.05 torque (N-m) torque (N-m) torque (N-m) 0.00 0.00 0.00

10.0

0.0

5.0

time (s)

10.0

5.0

time (s)

5.0

time (s)

10.0

0.0

0.0