

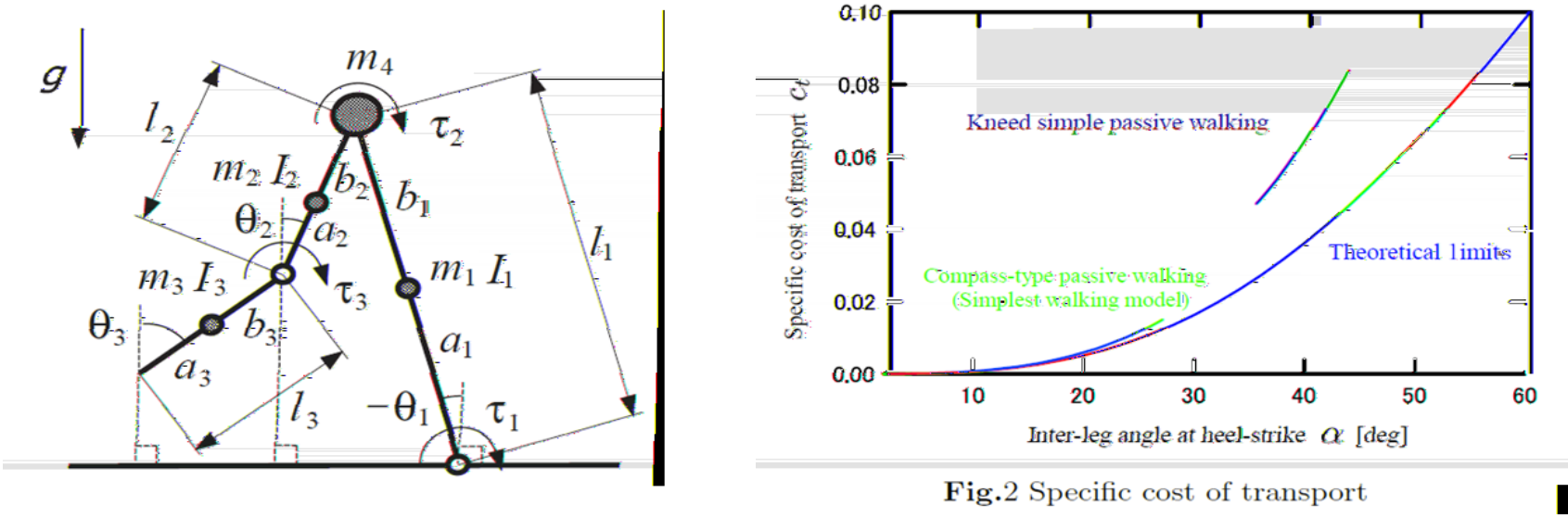
学会名	
演題名	
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内容	
関連画像	 <p>The figure consists of two parts. On the left is a schematic diagram of a three-link passive walking model. It shows a vertical line representing the ground with a downward arrow labeled g. A hip joint is at the top, with mass m_4. A thigh link of length l_1 and mass m_1 is attached to the hip, with its center of mass at distance a_1 from the hip and b_1 from the knee. A knee joint is at the end of the thigh, with mass m_2. A shank link of length l_2 and mass m_2 is attached to the knee, with its center of mass at distance a_2 from the knee and b_2 from the ankle. An ankle joint is at the end of the shank, with mass m_3. A foot link of length l_3 and mass m_3 is attached to the ankle, with its center of mass at distance a_3 from the ankle and b_3 from the heel. The heel is in contact with the ground. Angles θ_1, θ_2, and θ_3 are shown relative to the vertical. Torques τ_1, τ_2, and τ_3 are indicated at the joints.</p> <p>On the right is a graph showing the specific cost of transport c_t on the y-axis (ranging from 0.00 to 0.10) versus the inter-leg angle at heel-strike α [deg] on the x-axis (ranging from 10 to 60). A shaded gray region at the top of the graph is labeled "Kneed simple passive walking". A green curve is labeled "Compass-type passive walking (Simplest walking model)". A blue curve is labeled "Theoretical limits".</p>

Fig.2 Specific cost of transport