
Contents

Preface.....	xix
Author.....	xxi
Chapter 1 Introduction.....	1
1.1 Principal Areas of Biomechanics.....	1
1.2 Approach in This Book	2
References.....	2
Chapter 2 Review of Human Anatomy and Some Basic Terminology	7
2.1 Gross (Whole-Body) Modeling.....	7
2.2 Position and Direction Terminology	10
2.3 Terminology for Common Movements	14
2.4 Skeletal Anatomy	19
2.5 Major Joints	22
2.6 Major Muscle Groups	23
2.7 Anthropometric Data.....	24
References.....	26
Chapter 3 Methods of Analysis I: Review of Vectors, Dyadics, Matrices, and Determinants	29
3.1 Vectors	29
3.2 Vector Algebra: Addition and Multiplication by Scalars.....	30
3.2.1 Vector Characteristics	30
3.2.2 Equality of Vectors.....	30
3.2.3 Special Vectors.....	30
3.2.4 Multiplication of Vectors and Scalars	31
3.2.5 Vector Addition.....	32
3.2.6 Addition of Perpendicular Vectors.....	33
3.2.7 Use of Index and Summation Notations	36
3.3 Vector Algebra: Multiplication of Vectors.....	37
3.3.1 Angle between Vectors.....	37
3.3.2 Scalar Product.....	37
3.3.3 Vector Product.....	39
3.3.4 Dyadic Product.....	41
3.4 Dyadics	42
3.4.1 Zero Dyadic	42
3.4.2 Identity Dyadic.....	42
3.4.3 Dyadic Transpose.....	43
3.4.4 Symmetric Dyadics	43
3.4.5 Multiplication of Dyadics.....	43

3.4.6	Inverse Dyadics	44
3.4.7	Orthogonal Dyadics	44
3.5	Multiple Products of Vectors	44
3.5.1	Scalar Triple Product	45
3.5.2	Vector Triple Product	46
3.5.3	Dyadic/Vector Product	47
3.5.4	Other Multiple Products	48
3.6	Matrices/Arrays	48
3.6.1	Zero Matrices	49
3.6.2	Identity Matrices	49
3.6.3	Matrix Transpose	49
3.6.4	Equal Matrices	49
3.6.5	Symmetric Matrices	49
3.6.6	Skew-Symmetric Matrices	50
3.6.7	Diagonal Matrix	50
3.6.8	Matrix Measures	50
3.6.9	Singular Matrices	50
3.6.10	Multiplication of Matrices by Scalars	50
3.6.11	Addition of Matrices	50
3.6.12	Multiplication of Matrices	51
3.6.13	Inverse Matrices	51
3.6.14	Orthogonal Matrices	52
3.6.15	Submatrices	52
3.6.16	Rank	52
3.6.17	Partitioning of Matrices, Block-Multiplication	52
3.6.18	Pseudoinverse	53
3.7	Determinants	53
3.8	Relationship of 3×3 Determinants, Permutation Symbols, and Kronecker Delta Functions	55
3.9	Eigenvalues, Eigenvectors, and Principal Directions	59
3.10	Maximum and Minimum Eigenvalues and the Associated Eigenvectors	65
	References	66
	Bibliography	66
Chapter 4	Methods of Analysis II: Forces and Force Systems	69
4.1	Forces: Vector Representations	69
4.2	Moments of Forces	69
4.3	Moments of Forces about Lines	70
4.4	Systems of Forces	71
4.5	Special Force Systems	73
4.5.1	Zero Force Systems	73
4.5.2	Couples	74
4.5.3	Equivalent Force Systems	74
4.5.4	Superimposed and Negative Force Systems	77
4.6	Principle of Action-Reaction	77
	References	78

Chapter 5 Methods of Analysis III: Mechanics of Materials	79
5.1 Concepts of Stress	79
5.2 Concepts of Strain	84
5.3 Principal Values of Stress and Strain	88
5.4 A Two-Dimensional Example: Mohr's Circle	89
5.5 Elementary Stress-Strain Relations	94
5.6 General Stress-Strain (Constitutive) Relations	97
5.7 Equations of Equilibrium and Compatibility	99
5.8 Use of Curvilinear Coordinates	102
5.8.1 Cylindrical Coordinates	102
5.8.2 Spherical Coordinates	103
5.9 Review of Elementary Beam Theory	105
5.9.1 Sign Convention	105
5.9.2 Equilibrium Consideration	106
5.9.3 Strain-Curvature Relations	107
5.9.4 Stress-Bending Moment Relations	109
5.9.5 Summary of Governing Equations	110
5.10 Thick Beams	111
5.11 Curved Beams	114
5.12 Singularity Functions	115
5.13 Elementary Illustrative Examples	117
5.13.1 Cantilever Beam with a Concentrated End Load	117
5.13.2 Cantilever Beam with a Concentrated End Load on the Right End	120
5.13.3 Simply Supported Beam with a Concentrated Interior Span Load	122
5.13.4 Simply Supported Beam with Uniform Load	125
5.14 Listing of Selected Beam Displacement and Bending Moment Results	128
5.15 Magnitude of Transverse Shear Stress	129
5.16 Torsion of Bars	130
5.17 Torsion of Members with Noncircular and Thin-Walled Cross Sections	132
5.18 Energy Methods	133
References	139
Chapter 6 Methods of Analysis IV: Modeling of Biosystems	141
6.1 Multibody (Lumped Mass) Systems	141
6.2 Lower Body Arrays	142
6.3 Whole Body, Head/Neck, and Hand Models	146
6.4 Gross-Motion Modeling of Flexible Systems	150
References	151
Chapter 7 Tissue Biomechanics	153
7.1 Hard and Soft Tissue	153
7.2 Bones	154

7.3	Bone Cells and Microstructure.....	154
7.4	Physical Properties of Bone	155
7.5	Bone Development (Wolff's law).....	156
7.6	Bone Failure (Fracture and Osteoporosis).....	157
7.7	Muscle Tissue.....	158
7.8	Cartilage.....	159
7.9	Ligaments/Tendons	160
7.10	Scalp, Skull, and Brain Tissue	161
7.11	Skin Tissue	162
	References.....	163

Chapter 8 Kinematical Preliminaries: Fundamental Equations ... 165

8.1	Points, Particles, and Bodies.....	165
8.2	Particle, Position, and Reference Frames.....	166
8.3	Particle Velocity	166
8.4	Particle Acceleration	167
8.5	Absolute and Relative Velocity and Acceleration.....	169
8.6	Vector Differentiation, Angular Velocity.....	171
8.7	Two Useful Kinematic Procedures	176
8.7.1	Differentiation in Different Reference Frames	176
8.7.2	Addition Theorem for Angular Velocity	178
8.8	Configuration Graphs.....	180
8.9	Use of Configuration Graphs to Determine Angular Velocity	190
8.10	Application with Biosystems.....	192
8.11	Angular Acceleration.....	195
8.12	Transformation Matrix Derivatives.....	197
8.13	Relative Velocity and Acceleration of Two Points Fixed on a Body	199
8.14	Singularities Occurring with Angular Velocity Components and Orientation Angles	200
8.15	Rotation Dyadics.....	201
8.16	Euler Parameters	206
8.17	Euler Parameters and Angular Velocity	208
8.18	Inverse Relations between Angular Velocity and Euler Parameters	210
8.19	Numerical Integration of Governing Dynamical Equations.....	212
	References.....	213

Chapter 9 Kinematic Preliminaries: Inertia Force Considerations

9.1	Applied Forces and Inertia Forces.....	215
9.2	Mass Center.....	217
9.3	Equivalent Inertia Force Systems.....	221

Chapter 10 Human Body Inertia Properties

10.1	Second Moment Vectors, Moments, and Products of Inertia.....	225
10.2	Inertia Dyadics.....	229

10.3	Sets of Particles.....	230
10.4	Body Segments.....	232
10.5	Parallel Axis Theorem.....	234
10.6	Eigenvalues of Inertia: Principal Directions.....	237
10.7	Eigenvalues of Inertia: Symmetrical Bodies.....	241
10.8	Application with Human Body Models.....	243
	References.....	256
Chapter 11	Kinematics of Human Body Models.....	257
11.1	Notation, Degrees of Freedom, and Coordinates.....	257
11.2	Angular Velocities.....	261
11.3	Generalized Coordinates.....	266
11.4	Partial Angular Velocities.....	268
11.5	Transformation Matrices: Recursive Formulation.....	270
11.6	Generalized Speeds.....	273
11.7	Angular Velocities and Generalized Speeds.....	276
11.8	Angular Acceleration.....	279
11.9	Mass Center Positions.....	282
11.10	Mass Center Velocities.....	288
11.11	Mass Center Accelerations.....	290
11.12	Summary: Human Body Model Kinematics.....	291
	References.....	293
Chapter 12	Kinetics of Human Body Models.....	295
12.1	Applied (Active) and Inertia (Passive) Forces.....	295
12.2	Generalized Forces.....	297
12.3	Generalized Applied (Active) Forces on a Human Body Model.....	299
12.4	Forces Exerted across Articulating Joints.....	300
12.4.1	Contact Forces across Joints.....	301
12.4.2	Ligament and Tendon Forces.....	302
12.4.3	Joint Articulation Moments.....	304
12.5	Contribution of Gravity (Weight) Forces to the Generalized Active Forces.....	306
12.6	Generalized Inertia Forces.....	307
	References.....	309
Chapter 13	Dynamics of Human Body Models.....	311
13.1	Kane's Equations.....	311
13.2	Generalized Forces for a Human Body Model.....	312
13.3	Dynamical Equations.....	313
13.4	Formulation for Numerical Solutions.....	314
13.5	Constraint Equations.....	317
13.6	Constraint Forces.....	319
13.7	Constrained System Dynamics.....	322
13.8	Determination of Orthogonal Complement Arrays.....	324
13.9	Summary.....	325
	References.....	327

Chapter 14 Numerical Methods	329
14.1 Governing Equations	329
14.2 Numerical Development of the Governing Equations	331
14.3 Outline of Numerical Procedures	332
14.4 Algorithm Accuracy and Efficiency	333
Reference	335
Chapter 15 Simulations and Applications	337
15.1 Review of Human Modeling for Dynamic Simulation	337
15.2 A Human Body in Free-Space: A "Spacewalk"	339
15.2.1 X-Axis (Yaw) Rotation	340
15.2.2 Y-Axis (Pitch) Rotation	340
15.2.3 Z-Axis (Roll) Rotation	341
15.3 A Simple Weight Lift	342
15.4 Walking	344
15.4.1 Terminology	345
15.4.2 Modeling/Simulation	345
15.4.3 Results	346
15.5 Swimming	347
15.5.1 Modeling the Water Forces	347
15.5.2 Limb Motion Specification	348
15.5.3 Kick Strokes	349
15.5.4 Breast Stroke	350
15.5.5 Comments	350
15.6 Crash Victim Simulation I: Modeling	350
15.7 Crash Victim Simulation II: Vehicle Environment Modeling	351
15.8 Crash Victim Simulation III: Numerical Analysis	353
15.9 Burden Bearing—Waiter/Tray Simulations	354
15.9.1 Heavy Hanging Cable	354
15.9.2 Uniform Muscle Stress Criterion	356
15.9.3 Waitron/Tray Analysis	357
15.10 Other Applications	359
15.10.1 Load Sharing between Muscle Groups	360
15.10.2 Transition Movements	361
15.10.3 Gyroscopic Effects in Walking	361
15.10.4 Neck Injuries in Rollover Motor Vehicle Accidents	362
References	362
Appendix: Anthropometric Data Tables	367
Glossary	403
Bibliography	415
Index	419