```
|Hallux Definition|**1. Create RHal Segment:**\\ \\ <HTML><ol></HTML>\\
<HTML><li></HTML>In the **Segments** tab, select //RHal// in the Segment
Name box.<HTML></li></HTML>\\ <HTML><li></HTML>Select **Kinematic
Only**<HTML></li></HTML>\\ <HTML><li></HTML>Click on the **Create Segment**
button.<HTML></li></HTML>\\ <HTML><li></HTML>In the **RHal** tab, enter
these values:\\ \\ |<HTML><p></HTML>   **Define Proximal Joint and
Radius**\\    **Lateral:** //None//     **Joint:** //RFMH//     **Medial:**
//None//     \\    **Radius:** //0.1//\\ <HTML></p></HTML>\\ \\
<HTML><p></HTML>   **Define Distal Joint and Radius**\\    **Lateral:**
//None//     **Joint:** //RPM//     **Medial:** //None//     \\
   **Radius:** //0.1//\\ <HTML></p></HTML>\\ \\ <HTML><p></HTML>   **Extra
Target to Define Orientation**\\    **Location:**
//Lateral//     //RHal_Vert//\\ <HTML></p></HTML>\\ \\
<HTML><p></HTML>   **Select Tracking Targets:**\\      //RHal_Vert//,
//RFMH//, //RPM//\\ <HTML></p></HTML>||<HTML></li></HTML>\\
<HTML><li></HTML>Click on **Build Model.**<HTML></li></HTML>\\
<HTML><li></HTML>Click on **Close Tab** before
proceeding.<HTML></li></HTML><HTML></ol></HTML>  |
[[web/20201001125255/https://www.c-motion.com/v3dwiki/index.php?title=File:I
OR_Seg_RHal.png|{{/web/20201001125255im_/https://www.c-motion.com/v3dwiki/im
ages/thumb/3/3d/IOR_Seg_RHal.png/275px-
IOR_Seg_RHal.png?275x380|caption}}]]|\\ \\ \\ \\ \\ |**2. Modify the
[[web/20201001125255/https://www.c-motion.com/v3dwiki/index.php?title=Modify
_Segment_Coordinate_System#Modify_Segment_Coordinate_System|Segment
Coordinate System]]:**\\ \\ <HTML><ol></HTML>\\ <HTML><li></HTML>Define the
Segment Orientation as:\\ \\ |<HTML><p></HTML>   **A/P Axis:** //-Z//\\
   **Distal to Proximal:** //-X//\\
<HTML></p></HTML>||<HTML></li></HTML><HTML></ol></HTML>  |
[[web/20201001125255/https://www.c-motion.com/v3dwiki/index.php?title=File:I
OR_Seg_RHal_SCS.png|{{/web/20201001125255im_/https://www.c-motion.com/v3dwik
i/images/thumb/c/c8/IOR_Seg_RHal_SCS.png/275px-
IOR_Seg_RHal_SCS.png?275x132|caption}}]]|\\ \\ The image to the right (and
all other images in this tutorial) show a mediolateral view of the segment
coordinate system after it has been modified.|
```

Metatarsus (Met)

Segment Definition:

The FM2 landmark is projected onto the plane defined by the FM1, FM5, and SMB landmarks. The line from the SMB to FM2 projection are used to define the X axis (A/P) axis of the Met segment. The sagittal axis (Z axis) is along the plane defined by the FM1, FM5, and SMB targets.

The FMB target is not used to define the segment, but it will be used to track the segment (in addition to the other targets).

Joint Angles:

* Mid-Met Angle
* Cal-Met Angle
* F2Pt[1]/ Y component of the Met-Hal Angle[2]
* F2Ps[1]/ Z component of the Met-Hal Angle[2]

Planar Angles:

* S2F is projected onto the plane of the Met segment
* S2V is projected onto the plane of the Met segment

Metatarsus Landmarks											
1. Create RMET_DIST: • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RMET_DIST*	**Landmark Name:** *RMET_DIST* **Define Orientation Using:** **Starting Point:** *RFMH* **Ending Point:** *RVMH* **Lateral Object:** *RSMB* **Project From:** *RSMH*			• **Do NOT Check:** *Offset by Percent (1.0 = 100%)* • **Check:** *Calibration Only Landmark*							

Metatarsus Definition											
1. Create RMet Segment: • In the **Segments** tab, select *RMet* in the Segment Name box. • Select **Kinematic Only** • Click on the **Create Segment** button. • In the **RMet** tab, enter these values:	**Define Proximal Joint and Radius** **Lateral:** *None* **Joint:** *RSMB* **Medial:** *None* **Radius:** *0.1* **Define Distal Joint and Radius** **Lateral:** *None* **Joint:** *RMET_DIST* **Medial:** *None* **Radius:** *0.1* **Extra Target to Define Orientation Location:** *Medial RFMH* **Select Tracking Targets:** *RFMB*, *RFMH*, *RSMB*, *RSMH*, *RVMH*		• Click on **Build Model.** • Click on **Close Tab** before proceeding.		**2. Modify the Segment Coordinate System:** • Define the Segment Orientation as:		**A/P Axis:** *+Y* **Distal to Proximal:** *-X*		The image to the right (and all other images in this tutorial) show a mediolateral view of the segment coordinate system after it has been modified.	

Mid-foot (Mid)

Segment Definition: The midpoint between the TN and VMB targets is used to define the origin of the Mid segment. The A/P (X) axis is defined along the line from this midpoint to the SMB target. The sagittal (Z) axis is along the plane defined by the ID, TN and SMB targets. Joint Angles: * Cal-Mid Angle * Mid-Met Angle Planar Angles: * Not used for planar angles.

Mid-foot Landmarks								
1. Create RID Joint Center: • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RID*	**Landmark Name:** *RID* **Define Orientation Using:** **Starting Point:** *RTN* **Ending Point:** *RVMB*			• Offset Using the Following **AXIAL** Offset: *0.5* • **Check:** *Offset by Percent (1.0 = 100%)* • **Check:** *Calibration Only Landmark*				
Mid-foot Definition								
1. Create RMid Segment: • In the **Segments** tab, select *RMid* in the Segment Name box. • Select **Kinematic Only**. • Click on the **Create Segment** button. • In the **RMid** tab, enter these values:	**Define Proximal Joint and Radius** **Lateral:** *None* **Joint:** *RID* **Medial:** *None* **Radius:** *0.1* **Define Distal Joint and Radius** **Lateral:** *None* **Joint:** *RSMB* **Medial:** *None* **Radius:** *0.1* **Extra Target to Define Orientation** **Location:** *Medial RTN* **Select Tracking Targets:** *RSMB*, *RTN*, *RVMB*	• Click on **Build Model.** • Click on **Close Tab** before proceeding.		**2. Modify the Segment Coordinate System:** • Define the Segment Orientation as:	**A/P Axis:** *+Y* **Distal to Proximal:** *-X*			

Calcaneus (Cal)

Segment Definition: The origin is at the FCP target. The A/P (X) axis is along the line from the FCP to midpoint of the ST and PT targets (IC landmark). The sagittal (Z) axis is along the plane defined by the FCP, ST and TN targets. Joint Angles: * Sha-Cal Angle * Cal-Mid Angle Z rotation & Y Rotation* * Cal-Met Angle * The 2014 paper[2] modified the definition of inversion/eversion for the calcaneus segment relative to the shank segment. This is now calculated as the Sha_Cal_Fro angle which is a four point planar angle. Planar Angles: * No planar angles			
Calcaneus Landmarks			
1. Create RIC Joint Center: • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RIC*	**Landmark Name:** *RIC* **Define Orientation Using:** **Starting Point:** *RST* **Ending Point:** *RPT*	• Offset Using the Following **AXIAL** Offset: *0.5* • **Check:** *Offset by Percent (1.0 = 100%)* • **Check:** *Calibration Only Landmark*	
Calcaneus Definition			

1. Create RCal Segment: • In the **Segments** tab, select *RCal* in the Segment Name box. • Select **Kinematic Only** • Click on the **Create Segment** button. • In the **RCal** tab, enter these values:	**Define Proximal Joint and Radius** **Lateral:** *None* **Joint:** *RFCP* **Medial:** *None* **Radius:** *0.1* **Define Distal Joint and Radius** **Lateral:** *None* **Joint:** *RIC* **Medial:** *None* **Radius:** *0.1* **Extra Target to Define Orientation Location:** *Medial RST* **Select Tracking Targets:** *RFCP*, *RPT*, *RST*	• Click on **Build Model.** • Click on **Close Tab** before proceeding.		**2. Modify the Segment Coordinate System:** • Define the Segment Orientation as:	**A/P Axis:** *+Y* **Distal to Proximal:** *-X*	

Virtual Foot (Foo)

Segment Definition: The origin is at the FCP target. The A/P (X) axis is along the line from the FCP to RFT_DIST landmark. The sagittal (Z) axis is along the plane defined by the FCP, FMH and VMH targets. This foot segment should be set to “kinematic only” since the origin is not at the point of rotation (the mid point of the RIMM & RLM targets. The IORFoot analysis does not calculate kinetics, so no kinetic foot segment is described in this model. To create gait events, you will need a kinetic foot segment. An example of a kinetic foot segment is created in the sample download files for this tutorial.						
Foot Landmarks						
1. Create RFT_DIST: • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RFT_DIST*	**Landmark Name:** *RFT_DIST* **Define Orientation Using:** **Starting Point:** *RCA* **Ending Point:** *RFMH* **Lateral Object:** *RVMH* **Project From:** *RSMH*		• **Do NOT Check:** *Offset by Percent (1.0 = 100%)* • **Check:** *Calibration Only Landmark*			
Foot Definition						

1. Create Right Virtual Foot Segment: • In the **Segments** tab, select *Right Virtual Foot* in the Segment Name box. • Select **Kinematic Only** • Click on the **Create Segment** button. • In the **Right Virtual Foot** tab, enter these values:	**Define Proximal Joint and Radius** **Lateral:** *None* **Joint:** *RFCP* **Medial:** *None* **Radius:** *0.5*DISTANCE(RST,RPT)* **Define Distal Joint and Radius** **Lateral:** *None* **Joint:** *RFT_DIST* **Medial:** *None* **Radius:** *0.5*DISTANCE(RFMH,RVMH)* **Extra Target to Define Orientation** **Location:** *Medial* *RFMH* **Select Tracking Targets:** *RFCP*, *RFMH*, *RVMH*	• Click on **Build Model.** • Click on **Close Tab** before proceeding.		**2. Modify the Segment Coordinate System:** • Define the Segment Orientation as:	**A/P Axis:** *+Y* **Distal to Proximal:** *-X*	

Shank (Sha)

Shank Landmarks								
1. Create RIM: • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RIM*	**Landmark Name:** *RIM* **Define Orientation Using:** **Starting Point:** *RLM* **Ending Point:** *RMM*	• Offset Using the Following **AXIAL** Offset: *0.5* • **Check:** *Offset by Percent (1.0 = 100%)* • **Check:** *Calibration Only Landmark*		**2. Create RSK_PROX:** • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RSK_PROX*	**Landmark Name:** *RSK_PROX* **Define Orientation Using:** **Starting Point:** *RIM* **Ending Point:** *RLM* **Lateral Object:** *RHF* **Project From:** *RTT*	• **Do NOT Check:** *Offset by Percent (1.0 = 100%)* • **Check:** *Calibration Only Landmark*		
Shank Definition								

1. Create Right Shank Segment: • In the **Segments** tab, select *Right Shank* in the Segment Name box. • Click on the **Create Segment** button. • In the **Right Shank** tab, enter these values:	**Define Proximal Joint and Radius** **Lateral:** *None* **Joint:** *RSK_PROX* **Medial:** *None* **Radius:** *DISTANCE(RSK_PROX,RHF)* **Define Distal Joint and Radius** **Lateral:** *None* **Joint:** *RIM* **Medial:** *None* **Radius:** *0.5*DISTANCE(RLM,RMM)* **Extra Target to Define Orientation** **Location:** *Lateral RLM* **Select Tracking Targets:** *RHF*, *RLM*, *RMM*, *RTT*	• Click on **Build Model.** • Click on **Close Tab** before proceeding.		**2. Modify the Segment Coordinate System:** • Define the Segment Orientation as:	**A/P Axis:** *+X* **Distal to Proximal:** *+Y*	

Sagittal Planar Angles

The **F2G, S2G, and V2G** angles are planar angles relative to the ground.

The **MLA** angle is the angle between the Medial Longitudinal Arch/Navicular drop.

F2G S2G and V2G Landmarks

The F2G, S2G and V2G angles are calculated in the plane orthogonal to the ground. These landmarks will need to be projected onto the ground. To project landmarks onto the ground, the Lab_O, Lab_X and Lab_Y landmarks will need to be created to identify the plane of the ground.																										
F2G S2G and V2G Landmarks																										
1. Create Lab_O: • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *Lab_O*	**Landmark Name:** *Lab_O*	• Offset Using the Following **ML/AP/AXIAL** Offsets: **X:** *0.0* **Y:** *0.0* **Z:** *0.0* • **Do NOT Check:** *Offset by Percent (1.0 = 100%) (Meters when not checked)* • **Do NOT Check:** *Calibration Only Landmark (Not generated for assigned motion file(s))*		**2. Create Lab_X:** • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *Lab_X*	**Landmark Name:** *Lab_X*	• Offset Using the Following **ML/AP/AXIAL** Offsets: **X:** *0.05* **Y:** *0.0* **Z:** *0.0* • **Do NOT Check:** *Offset by Percent (1.0 = 100%) (Meters when not checked)* • **Do NOT Check:** *Calibration Only Landmark (Not generated for assigned motion file(s))*		**3. Create Lab_Y:** • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *Lab_Y*	**Landmark Name:** *Lab_Y*	• Offset Using the Following **ML/AP/AXIAL** Offsets: **X:** *0.0* **Y:** *0.05* **Z:** *0.0* • **Do NOT Check:** *Offset by Percent (1.0 = 100%) (Meters when not checked)* • **Do NOT Check:** *Calibration Only Landmark (Not generated for assigned motion file(s))*		**4. Create RFMH_proj:** • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RFMH_proj*	**Landmark Name:** *RFMH_proj* **Define Orientation Using: Starting Point:** *LAB_O* **Ending Point:** *LAB_X* **Lateral Object:** *LAB_Y* **Project From:** *RFMH*	• **Do NOT Check:** *Offset by Percent (1.0 = 100%)* • **Do NOT Check:** *Calibration Only Landmark*	**Create landmarks 7-17 by following the same format as the RFMH_proj landmark for:** ** **	5. RFMB 6. RSMH 7. RSMB 8. RVMH 9. RVMB	10. LFMH 11. LFMB 12. LSMH 13. LSMB 14. LVMH 15. LVMB	****

F2G Angle

F2G Angle – 3D angle of the first metatarsus relative to the ground				
F2G Definition				
1. Create RF2G planar angle: • Define **Resulting Signal** Name: *RF2G* • Calculate a **4 point angle** between the following targets:	1 - *TARGET::ORIGINAL::RFMB* 2 - *TARGET::ORIGINAL::RFMH* 3 - *TARGET::ORIGINAL::RFMH_proj* 4 - *TARGET::ORIGINAL::RFMB_proj* **Angle Direction:** *Right Hand Rule* **3D Space:** *Always 0 to 180 degrees*		**2. Create LF2G planar angle:** • When defining the left signal, use same definitions as for the right angle	

S2G Angle

S2G Angle – 3D angle of the second metatarsus relative to the ground				
S2G Definition				
1. Create RS2G planar angle: • Define **Resulting Signal** Name: *RS2G* • Calculate a **4 point angle** between the following targets:	1 - *TARGET::ORIGINAL::RSMB* 2 - *TARGET::ORIGINAL::RSMH* 3 - *TARGET::ORIGINAL::RSMH_proj* 4 - *TARGET::ORIGINAL::RSMB_proj* **Angle Direction:** *Right Hand Rule* **3D Space:** *Always 0 to 180 degrees*		**2. Create LS2G planar angle:** • When defining the left signal, use same definitions as for the right angle	

V2G Angle

V2G Angle – 3D angle of the fifth metatarsus relative to the ground				
V2G Definition				
1. Create RV2G planar angle: • Define **Resulting Signal** Name: *RV2G* • Calculate a **4 point angle** between the following targets:	1 - *TARGET::ORIGINAL::RVMB* 2 - *TARGET::ORIGINAL::RVMH* 3 - *TARGET::ORIGINAL::RVMH_proj* 4 - *TARGET::ORIGINAL::RVMB_proj* **Angle Direction:** *Right Hand Rule* **3D Space:** *Always 0 to 180 degrees*		**2. Create LV2G planar angle:** • When defining the left signal, use same definitions as for the right angle	

MLA Angle

MLA Angle – MLA Angle – Medial Longitudinal Arch/Navicular drop													
MLA Angle Landmarks													
The MLA angle is calculated using the proximal heel target projected onto the ground, tracked using the calcaneus segment. To accomplish this, two landmarks must be created: 1. The projection of the proximal heel target onto the ground 2. Track the proximal heel target projection using the calcaneus segment To create these landmarks, the **LAB_O, LAB_X and LAB_Y** landmarks must be created and the calcaneus segment must be defined.	**NOTE:** The image for the MLA Angle shows the PROCESSED target folder being used for the signal definition. If you have used the ORIGINAL target data for the other planar angles, you should continue to use the ORIGINAL folder.	**1. Create RFCP_proj:** • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RFCP_proj*	**Landmark Name:** *RFCP_proj* **Define Orientation Using:** **Starting Point:** *LAB_O* **Ending Point:** *LAB_X* **Lateral Object:** *LAB_Y* **Project From:** *RFCP*	• **Do NOT Check:** *Offset by Percent (1.0 = 100%)* • **Check:** *Calibration Only Landmark*		**2. Create LFCP_proj:** - Use the same definition as the RFCP_proj, but use left side target	**3. Create RFCP_proj_track:** • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RFCP_track*	**Landmark Name:** *RFCP_proj_track* **Define Orientation Using:** **Starting Point:** *RFCP_proj* Click **Existing Segment:** *RCal*	• **Do NOT Check:** *Offset by Percent (1.0 = 100%)* • **Do NOT Check:** *Calibration Only Landmark*		**4. Create LFCP_proj_track:** - Use the same definition as the RFCP_proj_track, but use left side landmark/segment

MLA Definition					

1. Create RMLA planar angle: • Define **Resulting Signal** Name: *RMLA* • Calculate a **3 point angle** between the following targets:	1 - *LANDMARK::ORIGINAL::RFCP_track* 2 - *TARGET::ORIGINAL::RST* 3 - *TARGET::ORIGINAL::RFMH* **Angle Direction:** *Right Hand Rule* **Use Range:** *-180 to 180 degrees* **Projected onto Plane:** *XY* **Note: The reference segment will need to be changed to *RMF* within the text option.** Command text should have the internal name (e.g. RMF) and not the display name “Right Virtual Foot”. https:%%//%%www.c-motion.com/v3dwiki/index.php?title=Segment_Default_Names		**2. Create LMLA planar angle:** • When defining the left signal, use same definitions as for the right angle	**Note: The reference segment will need to be changed to *Left Virtual Foot* within the text option.**	

Transverse Planar Angles

S2F Angle

S2F Angle – Angle between the first and second metatarsus projected on to the transverse plane of the Met segment					
S2F Definition					
1. Create RS2F planar angle: • Define **Resulting Signal** Name: *RS2F* • Calculate a **4 point angle** between the following targets:	1 - *TARGET::ORIGINAL::RSMH* 2 - *TARGET::ORIGINAL::RSMB* 3 - *TARGET::ORIGINAL::RFMB* 4 - *TARGET::ORIGINAL::RFMH* **Angle Direction:** *Right Hand Rule* **Use Range:** *-180 to 180 degrees* **Projected onto Plane:** *XZ* **Note: The reference segment will need to be changed to *RMet* within the text option.**		**2. Create LS2F planar angle:** • When defining the left signal, use same definitions **except** set:	**Angle Direction:** *Left Hand Rule* **Note: The reference segment will need to be changed to *LMet* within the text option.**	

S2V Angle

S2V Angle – Angle between the fifth and second metatarsus projected on to the transverse plane of the Met segment					
S2V Definition					

1. Create RS2V planar angle: • Define **Resulting Signal** Name: *RS2V* • Calculate a **4 point angle** between the following targets:	1 - *TARGET::ORIGINAL::RSMH* 2 - *TARGET::ORIGINAL::RSMB* 3 - *TARGET::ORIGINAL::RVMB* 4 - *TARGET::ORIGINAL::RVMH* **Angle Direction:** *Left Hand Rule* **Use Range:** *-180 to 180 degrees* **Projected onto Plane:** *XZ* **Note: The reference segment will need to be changed to *RMet* within the text option.**		**2. Create LS2V planar angle:** • When defining the left signal, use same definitions **except** set:	**Angle Direction:** *Right Hand Rule* **Note: The reference segment will need to be changed to *LMet* within the text option.**

Calcaneus Inv/Eve

Sha_Cal_Frontal Angle – Angle of the calcaneus segment relative to the shank segment This planar angle will be used to replace the inversion/eversion angle of the Sha_Cal joint angle 0 degrees indicates the calcaneus is aligned with the shank.

Sha_Cal_Frontal Landmarks											
1. Create RSK_PROX_track: • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RSK_PROX_track*	**Landmark Name:** *RSK_PROX_track* **Define Orientation Using:** Click **Existing Segment:** *RSK*	• Offset Using the Following **ML/AP/AXIAL** Offsets: **X:** *0.0* **Y:** *0.0* **Z:** *0.0* • **Check:** *Offset by Percent (1.0 = 100%)* • **Do NOT Check:** *Calibration Only Landmark*	**2. Create RSK_DIST_track:** • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RSK_DIST_track*	**Landmark Name:** *RSK_DIST_track* **Define Orientation Using:** Click **Existing Segment:** *RSK*	• Offset Using the Following **ML/AP/AXIAL** Offsets: **X:** *0.0* **Y:** *0.0* **Z:** *-1.0* • **Check:** *Offset by Percent (1.0 = 100%)* • **Do NOT Check:** *Calibration Only Landmark*	**3. Create RFCD_track Joint Center:** • Click **Landmarks** button • Click **Add New Landmark** button • Create Landmark: *RFCD_track*	**Landmark Name:** *RFCD_track* **Define Orientation Using:** Click **Existing Segment:** *RCal*	• Offset to Existing Calibration Target or Landmark: *RFCD* • **Do NOT Check:** *Offset by Percent (1.0 = 100%)* • **Do NOT Check:** *Calibration Only Landmark*		
Sha_Cal_Frontal Definition											

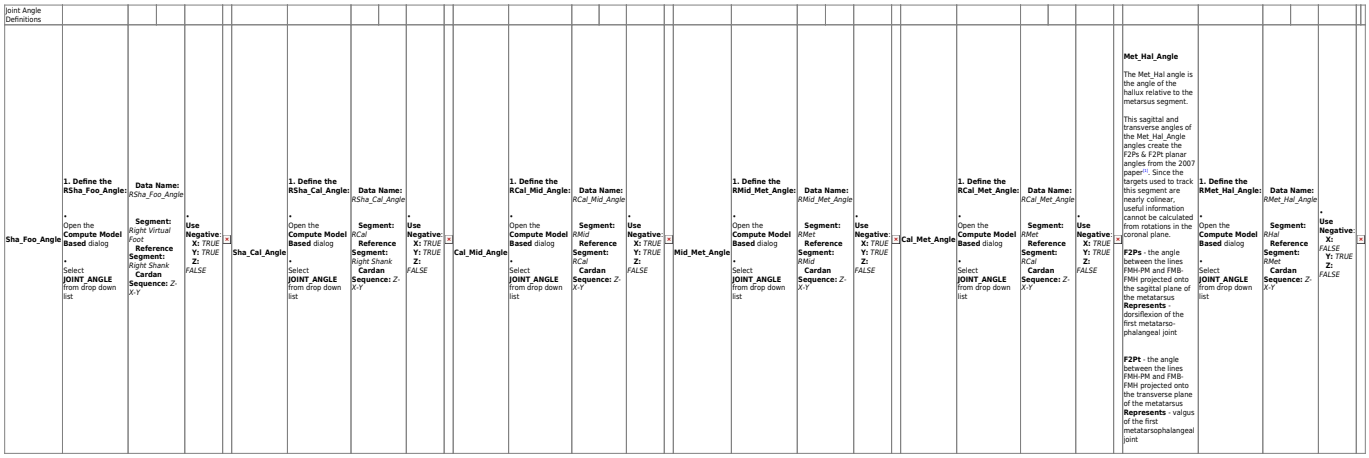
1. Create RSha_Cal_Fro planar angle: • Define **Resulting Signal** Name: *RSha_Cal_Fro* • Calculate a **4 point angle** between the following targets:	1 - *LANDMARK::ORIGINAL::RSK_PROX_TRACK* 2 - *LANDMARK::ORIGINAL::RSK_DIST_TRACK* 3 - *LANDMARK::ORIGINAL::RFCD_TRACK* 4 - *TARGET::ORIGINAL::RFCP* **Angle Direction:** *Left Hand Rule* **Use Range:** *-180 to 180 degrees* **Projected onto Plane:** *YZ* **Note: The reference segment will need to be changed to *RSK* within the text option.**		**2. Create LSha_Cal_Fro planar angle:** • When defining the left signal, use same definitions **except** set:	**Angle Direction:** *Right Hand Rule* **Note: The reference segment will need to be changed to *LSK* within the text option.**

Joint Angles

Joint Angle definitions for the:

- Sha_Foo_Angle
- Sha_Cal_Angle
- Cal_Mid_Angle
- Mid_Met_Angle
- Cal_Met_Angle
- Met_Hal_Angle

The Met_Hal_Angle calculations are used to replace the F2Ps & F2Pt planar angles from the 2007 paper[1].



References

1. ↑ 1.00 1.01 1.02 1.03 1.04 1.05 1.06 1.07 1.08 1.09 1.10 1.11 1.12 1.13 1.14 1.15 1.16 1.17 1.18 1.19 1.20 1.21 1.22 1.23 1.24 1.25 1.26 1.27 1.28 Leardini, A., M.G. Benedetti, L. Berti, D. Bettinelli, R. Nativo, and S. Giannini. “Rear-foot, Mid-foot and Fore-foot Motion during the Stance Phase of Gait.” Gait & Posture 25 (2007): 453-55
2. ↑ 2.00 2.01 2.02 2.03 2.04 2.05 2.06 2.07 2.08 2.09 2.10 2.11 2.12 2.13 Portinaro, N., A. Leardini, A. Panou, V. Monzani, and P. Caravaggi. “Modifying the Rizzoli foot model to improve the diagnosis of pes-planus: application to kinematics of feet in teenagers.” Journal of Foot and Ankle Research (2014)

3. ↑ 3.00 3.01 3.02 3.03 3.04 3.05 3.06 3.07 3.08 3.09 3.10 3.11 3.12 3.13 3.14 3.15 Serge van Sint Jan “Color Atlas of Skeletal Landmark Definitions: Guidelines for Reproducible Manual and Virtual Palpations” 2007 - Churchill Livingstone

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