```xml
<mujoco model="template">
  <!-- This model has been converted from an OpenSim model. Model conversion by
MyoConverter https://github.com/MyoHub/myoconverter. This model is licensed
under Apache 2.0. -->
  <compiler angle="radian" autolimits="true"/>
  <option timestep="0.005" collision="predefined"/>
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  <visual>
    <scale framelength="0.5" framewidth="0.01"/>
  </visual>
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    <geom margin="0.001" rgba="0.8 0.6 0.4 1"/>
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0.5 1.6 1.5 1.3 1.2 0" biasprm="0.75 1.05 -1 200 0.5 1.6 1.5 1.3 1.2 0"/>
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    <default class="motor">
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    <texture type="skybox" builtin="gradient" rgb1="1 1 1" rgb2="0.6 0.8 1"
width="256" height="1536"/>
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    <mesh name="pelvis_geom_2_l_pelvis" file="Geometry/l_pelvis.stl"/>
    <mesh name="pelvis_geom_3_sacrum" file="Geometry/sacrum.stl"/>
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    <mesh name="tibia_r_geom_1_r_tibia" file="Geometry/r_tibia.stl"/>
    <mesh name="tibia_r_geom_2_r_fibula" file="Geometry/r_fibula.stl"/>
    <mesh name="talus_r_geom_1_r_talus" file="Geometry/r_talus.stl"/>
    <mesh name="calcn_r_geom_1_r_foot" file="Geometry/r_foot.stl"/>
    <mesh name="toes_r_geom_1_r_bofoot" file="Geometry/r_bofoot.stl"/>
    <mesh name="patella_r_geom_1_r_patella" file="Geometry/r_patella.stl"/>
    <mesh name="femur_l_geom_1_l_femur" file="Geometry/l_femur.stl"/>
    <mesh name="tibia_l_geom_1_l_tibia" file="Geometry/l_tibia.stl"/>
    <mesh name="tibia_l_geom_2_l_fibula" file="Geometry/l_fibula.stl"/>
    <mesh name="talus_l_geom_1_l_talus" file="Geometry/l_talus.stl"/>
    <mesh name="calcn_l_geom_1_l_foot" file="Geometry/l_foot.stl"/>
    <mesh name="toes_l_geom_1_l_bofoot" file="Geometry/l_bofoot.stl"/>
    <mesh name="patella_l_geom_1_l_patella" file="Geometry/l_patella.stl"/>
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    <mesh name="torso_geom_2_hat_jaw" file="Geometry/hat_jaw.stl"/>
    <mesh name="torso_geom_3_hat_skull" file="Geometry/hat_skull.stl"/>
    <mesh name="torso_geom_4_hat_ribs_scap" file="Geometry/hat_ribs_scap.stl"/>
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    <mesh name="hand_r_geom_22_little_proximal_rvs" file="Geometry/little_proximal_rvs.stl" scale="0.85 0.85 0.85"/>
    <mesh name="hand_r_geom_23_little_medial_rvs" file="Geometry/little_medial_rvs.stl" scale="0.85 0.85 0.85"/>
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    <mesh name="hand_l_geom_25_metacarpal1_lvs" file="Geometry/
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    <mesh name="hand_l_geom_26_thumb_proximal_lvs" file="Geometry/
thumb_proximal_lvs.stl" scale="0.85 0.85 0.85"/>
    <mesh name="hand_l_geom_27_thumb_distal_lvs" file="Geometry/
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    </body>
    <body name="pelvis" quat="0.707035 0.707179 0 0">
     <inertial pos="-0.0707 0 0" mass="11.777" diaginertia="0.1028 0.0871 0.0579"/>
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damping="0"/>
     <joint name="pelvis_ty" pos="0 0 0" axis="0 1 0" type="slide" range="-1 2"
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     <joint name="pelvis_tz" pos="0 0 0" axis="0 0 1" type="slide" range="-3 3"
damping="0"/>
     <joint name="pelvis_tilt" pos="0 0 0" axis="0 0 1" range="-1.571 1.571"
damping="0"/>
     <joint name="pelvis_list" pos="0 0 0" axis="1 0 0" range="-1.571 1.571"
damping="0"/>
     <joint name="pelvis_rotation" pos="0 0 0" axis="0 1 0" range="-1.571 1.571"
damping="0"/>
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mesh="pelvis_geom_1_r_pelvis"/>
     <geom name="pelvis_geom_2" type="mesh" rgba="1 1 1 1"
mesh="pelvis_geom_2_l_pelvis"/>
     <geom name="pelvis_geom_3" type="mesh" rgba="1 1 1 1"
mesh="pelvis_geom_3_sacrum"/>
     <geom name="Gmax1_at_pelvis_r_cylinder" size="0.04 0.075" pos="-0.077
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group="2" rgba="0.19 0.83 0.78 0.2"/>
     <geom name="Gmax2_at_pelvis_r_cylinder" size="0.04 0.05" pos="-0.08 -0.083
0.068" quat="0.912872 -0.359331 0.180301 -0.0709714" type="cylinder" group="2"
rgba="0.19 0.83 0.78 0.2"/>
     <geom name="Gmax3_at_pelvis_r_cylinder" size="0.04 0.05" pos="-0.083
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0.83 0.78 0.2"/>
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group="2" rgba="0.19 0.83 0.78 0.2"/>
<geom name="Gmax2_at_pelvis_l_cylinder" size="0.04 0.05" pos="-0.08 -0.083
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rgba="0.19 0.83 0.78 0.2"/>
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0.83 0.78 0.2"/>
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<site name="addmagProx_r_addmagProx_r-P1" pos="-0.03098 -0.10755
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0.312 0.332" size="0.0005"/>
    <site name="glmed1_l_glmed1_l-P1" pos="-0.0445 0.0245 -0.1172"/>
    <site name="glmed2_l_glmed2_l-P1" pos="-0.085 0.0316 -0.0675"/>
    <site name="glmed3_l_glmed3_l-P1" pos="-0.1152 -0.0073 -0.0526"/>
    <site name="glmin1_l_glmin1_l-P1" pos="-0.0464 -0.0149 -0.1042"/>
    <site name="glmin2_l_glmin2_l-P1" pos="-0.0616 -0.0142 -0.0971"/>
    <site name="glmin3_l_glmin3_l-P1" pos="-0.0789 -0.0155 -0.0798"/>
    <site name="grac_l_grac_l-P1" pos="-0.04736 -0.12932 -0.02456"/>
    <site name="iliacus_l_iliacus_l-P1" pos="-0.0605 0.0309 -0.0843"/>
    <site name="iliacus_l_iliacus_l-P2" pos="-0.0135 -0.0557 -0.0756"/>
    <site name="IL_at_brim_l_cylinder_iliacus_l_2_sidesite" pos="-0.00956006
-0.0694537 -0.0998035" size="0.0005"/>
    <site name="piri_l_piri_l-P1" pos="-0.10181 -0.00653 -0.01351"/>
    <site name="piri_l_piri_l-P2" pos="-0.10202 -0.03066 -0.06092"/>
    <site name="psoas_l_psoas_l-P1" pos="-0.0606 0.062 -0.039"/>
    <site name="psoas_l_psoas_l-P2" pos="-0.0205 -0.0654 -0.0656"/>
    <site name="PS_at_brim_l_cylinder_psoas_l_2_sidesite" pos="-0.0249699
-0.0765418 -0.0991876" size="0.0005"/>
    <site name="recfem_l_recfem_l-P1" pos="-0.024 -0.0388 -0.0933"/>
    <site name="sart_l_sart_l-P1" pos="-0.0195 -0.0156 -0.1056"/>
    <site name="semimem_l_semimem_l-P1" pos="-0.0987 -0.114 -0.0614"/>
    <site name="semiten_l_semiten_l-P1" pos="-0.1038 -0.1253 -0.0515"/>
    <site name="tfl_l_tfl_l-P1" pos="-0.0311 0.0214 -0.1241"/>
    <site name="RASI_marker" pos="0.00953 0.01808 0.1285" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
    <site name="LASI_marker" pos="0.00953 0.01808 -0.1285" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
    <site name="RPSI_marker" pos="-0.155 0.035 0.045" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
    <site name="LPSI_marker" pos="-0.155 0.035 -0.045" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
    <body name="femur_r" pos="-0.05628 -0.07849 0.07726">
    <inertial pos="0 -0.17 0" quat="0.5 0.5 -0.5 0.5" mass="9.3014"
diaginertia="0.1412 0.1339 0.0351"/>
    <joint name="hip_flexion_r" pos="0 0 0" axis="0 0 1" range="-0.5236 2.094"/>
    <joint name="hip_adduction_r" pos="0 0 0" axis="1 0 0" range="-0.8727
0.5236"/>
    <joint name="hip_rotation_r" pos="0 0 0" axis="0 1 0" range="-0.6981 0.6981"/>
    <geom name="femur_r_geom_1" type="mesh" rgba="1 1 1 1"
mesh="femur_r_geom_1_r_femur"/>
    <geom name="Gastroc_at_condyles_r_cylinder" size="0.025 0.05" pos="0.005
-0.41 0" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="KnExt_at_fem_r_cylinder" size="0.025 0.05" pos="0.003588
-0.4027 0.002091" quat="0.999192 -0.0311549 0.0253649 -0.000790882"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AB_at_femshaft_r_cylinder" size="0.0165 0.035" pos="0.01464
-0.1126 0.02337" quat="0.671205 0.735393 0.0628058 0.068812" type="cylinder"
group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AL_at_femshaft_r_cylinder" size="0.0201 0.05" pos="0.03073
-0.2319 0.01511" quat="0.629109 0.77432 0.0430035 0.0529295" type="cylinder"
```

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group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AMprox_at_femshaft_r_cylinder" size="0.0211 0.035"
pos="0.005183 -0.07289 0.0254" quat="0.689738 0.718041 0.0645399 0.0671882"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AMmid_at_femshaft_r_cylinder" size="0.0214 0.06"
pos="0.02301 -0.1607 0.02058" quat="0.691136 0.719496 0.0472781 0.0492181"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AMdist_at_femshaft_r_cylinder" size="0.0218 0.1"
pos="0.03161 -0.2607 0.009365" quat="0.652613 0.751942 0.0610661 0.0703605"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AMisch_at_condyles_r_cylinder" size="0.04 0.12"
pos="-0.02265 -0.3768 -0.003154" quat="0.638315 0.734726 -0.150602 -0.173349"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="PECT_at_femshaft_r_cylinder" size="0.015 0.025"
pos="0.006086 -0.0845 0.03044" quat="0.610631 0.779849 0.0848995 0.108427"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <site name="addbrev_r_addbrev_r-P2" pos="-0.002 -0.118 0.0249"/>
    <site name="AB_at_femshaft_r_cylinder_addbrev_r_1_sidesite"
pos="-0.00298132 -0.0891803 0.0106948" size="0.0005"/>
    <site name="addlong_r_addlong_r-P2" pos="0.01126 -0.23937 0.01583"/>
    <site name="AL_at_femshaft_r_cylinder_addlong_r_1_sidesite" pos="0.01126
-0.2394 0.01583" size="0.0005"/>
    <site name="addmagDist_r_addmagDist_r-P2" pos="0.01125 -0.2625 0.0193"/
>
    <site name="AMdist_at_femshaft_r_cylinder_addmagDist_r_1_sidesite"
pos="0.00727129 -0.270142 0.0137612" size="0.0005"/>
    <site name="addmagIsch_r_addmagIsch_r-P2" pos="0.00481 -0.38797
-0.03273"/>
    <site name="AMisch_at_condyles_r_cylinder_addmagIsch_r_1_sidesite"
pos="0.00481 -0.388 -0.03273" size="0.0005"/>
    <site name="addmagMid_r_addmagMid_r-P2" pos="0.00242 -0.1624 0.02922"/
>
    <site name="AMmid_at_femshaft_r_cylinder_addmagMid_r_1_sidesite"
pos="0.00242 -0.1624 0.02922" size="0.0005"/>
    <site name="addmagProx_r_addmagProx_r-P2" pos="-0.01527 -0.07886
0.03202"/>
    <site name="AMprox_at_femshaft_r_cylinder_addmagProx_r_1_sidesite"
pos="-0.00450528 -0.0803332 0.00231129" size="0.0005"/>
    <site name="bfsh_r_bfsh_r-P1" pos="0.005 -0.2111 0.0234"/>
    <site name="gaslat_r_gaslat_r-P1" pos="-0.003 -0.3814 0.0277"/>
    <site name="Gastroc_at_condyles_r_cylinder_gaslat_r_1_sidesite"
pos="-0.0245562 -0.415141 -0.0281762" size="0.0005"/>
    <site name="gasmed_r_gasmed_r-P1" pos="0.008 -0.3788 -0.0208"/>
    <site name="Gastroc_at_condyles_r_cylinder_gasmed_r_1_sidesite"
pos="-0.015562 -0.388155 0.0489792" size="0.0005"/>
    <site name="glmax1_r_glmax1_r-P3" pos="-0.0444 -0.0326 0.0302"/>
    <site name="glmax1_r_glmax1_r-P4" pos="-0.0277 -0.0566 0.047"/>
    <site name="glmax2_r_glmax2_r-P3" pos="-0.045 -0.0584 0.0252"/>
    <site name="glmax2_r_glmax2_r-P4" pos="-0.0156 -0.1016 0.0419"/>
    <site name="glmax3_r_glmax3_r-P3" pos="-0.0281 -0.1125 0.0094"/>
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<site name="glmax3_r_glmax3_r-P4" pos="-0.006 -0.1419 0.0411"/>
<site name="glmed1_r_glmed1_r-P2" pos="-0.0218 -0.0117 0.0555"/>
<site name="glmed2_r_glmed2_r-P2" pos="-0.0258 -0.0058 0.0527"/>
<site name="glmed3_r_glmed3_r-P2" pos="-0.0309 -0.0047 0.0518"/>
<site name="glmin1_r_glmin1_r-P2" pos="-0.0072 -0.0104 0.056"/>
<site name="glmin2_r_glmin2_r-P2" pos="-0.0096 -0.0104 0.056"/>
<site name="glmin3_r_glmin3_r-P2" pos="-0.0135 -0.0083 0.055"/>
<site name="iliacus_r_iliacus_r-P3" pos="-0.0023 -0.0565 0.0139"/>
<site name="iliacus_r_iliacus_r-P4" pos="-0.0122 -0.0637 0.0196"/>
<site name="piri_r_piri_r-P3" pos="-0.0148 -0.0036 0.0437"/>
<site name="psoas_r_psoas_r-P3" pos="-0.0132 -0.0467 0.0046"/>
<site name="psoas_r_psoas_r-P4" pos="-0.0235 -0.0524 0.0088"/>
<site name="KnExt_at_fem_r_cylinder_recfem_r_3_sidesite" pos="0.253588
-0.1527 0.252091" size="0.0005"/>
<site name="sart_r_sart_r-P2" pos="-0.003 -0.3568 -0.0421"/>
<site name="tfl_r_tfl_r-P2" pos="0.0294 -0.0995 0.0597"/>
<site name="tfl_r_tfl_r-P3" pos="0.0107 -0.405 0.0324"/>
<site name="vasint_r_vasint_r-P1" pos="0.029 -0.1924 0.031"/>
<site name="vasint_r_vasint_r-P2" pos="0.0335 -0.2084 0.0285"/>
<site name="KnExt_at_fem_r_cylinder_vasint_r_3_sidesite" pos="0.253588
-0.1527 0.252091" size="0.0005"/>
<site name="vaslat_r_vaslat_r-P1" pos="0.0048 -0.1854 0.0349"/>
<site name="vaslat_r_vaslat_r-P2" pos="0.0269 -0.2591 0.0409"/>
<site name="KnExt_at_fem_r_cylinder_vaslat_r_3_sidesite" pos="0.253588
-0.1527 0.252091" size="0.0005"/>
<site name="vasmed_r_vasmed_r-P1" pos="0.014 -0.2099 0.0188"/>
<site name="vasmed_r_vasmed_r-P2" pos="0.0356 -0.2769 0.0009"/>
<site name="KnExt_at_fem_r_cylinder_vasmed_r_4_sidesite" pos="-0.007846
-0.4075 -0.02075" size="0.0005"/>
<site name="KnExt_at_fem_r_cylinder_vasmed_r_3_sidesite" pos="-0.007846
-0.4075 -0.02075" size="0.0005"/>
<site name="RHJC_marker" pos="0 0 0" size="0.01" group="4" rgba="1 0.1 0.5
0.5"/>
<site name="RTH1_marker" pos="0.018 -0.15 0.064" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="RTH2_marker" pos="0.08 -0.23 0.0047" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="RTH3_marker" pos="0.01 -0.3 0.06" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="RLFC_marker" pos="0 -0.404 0.05" size="0.01" group="4" rgba="1
0.1 0.5 0.5"/>
<site name="RMFC_marker" pos="0 -0.404 -0.05" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<body name="tibia_r" pos="-4.6e-07 -0.4044 -0.001265">
  <inertial pos="0 -0.1867 0" quat="0.5 0.5 -0.5 0.5" mass="3.7075"
diaginertia="0.0511 0.0504 0.0051"/>
  <joint name="walker_knee_r_translation1" pos="0 0 0" axis="-0.124295
0.989762 -0.0701573" type="slide" range="0 0.001599" user="9.53733e-08"/>
  <joint name="walker_knee_r_translation2" pos="0 0 0" axis="0.992243
0.124005 -0.00878938" type="slide" range="0 0.006792" user="7.69254e-11"/>
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```xml
<joint name="knee_angle_r" pos="0 0 0" axis="-4.56599e-07 -0.0707098
-0.997497" range="0 2.094"/>
<joint name="walker_knee_r_rotation2" pos="0 0 0" axis="0.992243 0.124005
-0.00878938" range="-0.001678 0.03354" user="-1.47325e-08"/>
<joint name="walker_knee_r_rotation3" pos="0 0 0" axis="-0.124295 0.989762
-0.0701573" range="0 0.2628" user="1.08939e-08"/>
<geom name="tibia_r_geom_1" type="mesh" rgba="1 1 1 1"
mesh="tibia_r_geom_1_r_tibia"/>
<geom name="tibia_r_geom_2" type="mesh" rgba="1 1 1 1"
mesh="tibia_r_geom_2_r_fibula"/>
<geom name="GasLat_at_shank_r_cylinder" size="0.055 0.05" pos="-0.0074
-0.074 -0.0033" quat="-0.0297182 0.737325 0.65545 -0.160791" type="cylinder"
group="2" rgba="0.19 0.83 0.78 0.2"/>
<geom name="GasMed_at_shank_r_cylinder" size="0.055 0.05" pos="-0.0074
-0.074 -0.0033" quat="0.0738196 0.735435 0.67182 -0.0484208" type="cylinder"
group="2" rgba="0.19 0.83 0.78 0.2"/>
<geom name="GR_at_condyles_r_cylinder" size="0.036 0.05" pos="-0.003
-0.02 0" quat="0.980067 0 -0.198669 0" type="cylinder" group="2" rgba="0.19 0.83
0.78 0.2"/>
<geom name="SM_at_condyles_r_cylinder" size="0.0352 0.05" pos="-0.001
-0.02 0" quat="0.99875 0 -0.0499792 0" type="cylinder" group="2" rgba="0.19 0.83
0.78 0.2"/>
<geom name="ST_at_condyles_r_cylinder" size="0.0425 0.05" pos="-0.002
-0.0205 0" quat="0.995004 0 -0.0998334 0" type="cylinder" group="2" rgba="0.19
0.83 0.78 0.2"/>
<geom name="BF_at_gastroc_r_cylinder" size="0.03 0.075" pos="-0.058
-0.06 0" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
<site name="GasLat_at_shank_r_sidesite" pos="-0.06099 -0.06623 0.01096"
size="0.0005"/>
<site name="GasMed_at_shank_r_sidesite" pos="-0.06314 -0.06917
-0.005735" size="0.0005"/>
<site name="BF_at_gastroc_r_sidesite" pos="-0.058 -0.029 0" size="0.0005"/>
<site name="bflh_r_bflh_r-P2" pos="-0.0337 -0.035 0.0253"/>
<site name="bflh_r_bflh_r-P3" pos="-0.0287 -0.0455 0.0303"/>
<site name="bfsh_r_bfsh_r-P2" pos="-0.0301 -0.0419 0.0318"/>
<site name="edl_r_edl_r-P1" pos="-0.016 -0.1157 0.0205"/>
<site name="edl_r_edl_r-P2" pos="0.0164 -0.376 0.0112"/>
<site name="ehl_r_ehl_r-P1" pos="-0.014 -0.155 0.0189"/>
<site name="ehl_r_ehl_r-P2" pos="0.0071 -0.2909 0.0164"/>
<site name="ehl_r_ehl_r-P3" pos="0.02 -0.3693 -0.0028"/>
<site name="fdl_r_fdl_r-P1" pos="-0.0023 -0.1832 -0.0018"/>
<site name="fdl_r_fdl_r-P2" pos="-0.0176 -0.3645 -0.0124"/>
<site name="fhl_r_fhl_r-P1" pos="-0.031 -0.2163 0.02"/>
<site name="fhl_r_fhl_r-P2" pos="-0.0242 -0.3671 -0.0076"/>
<site name="grac_r_grac_r-P2" pos="-0.01842 -0.04755 -0.02961"/>
<site name="grac_r_grac_r-P3" pos="0.00178 -0.06962 -0.01573"/>
<site name="GR_at_condyles_r_cylinder_grac_r_1_sidesite"
pos="-0.0203029 -0.00232331 -0.0602976" size="0.0005"/>
<site name="perbrev_r_perbrev_r-P1" pos="-0.0243 -0.2532 0.0251"/>
<site name="perbrev_r_perbrev_r-P2" pos="-0.0339 -0.3893 0.0249"/>
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```xml
<site name="perbrev_r_perbrev_r-P3" pos="-0.0285 -0.4004 0.0255"/>
<site name="perlong_r_perlong_r-P1" pos="-0.02 -0.1373 0.0282"/>
<site name="perlong_r_perlong_r-P2" pos="-0.0317 -0.39 0.0237"/>
<site name="perlong_r_perlong_r-P3" pos="-0.0272 -0.4014 0.024"/>
<site name="recfem_r_recfem_r-P5" pos="0.0326 -0.06312 -0.00047"/>
<site name="sart_r_sart_r-P3" pos="-0.0251 -0.0401 -0.0365"/>
<site name="sart_r_sart_r-P4" pos="-0.0159 -0.0599 -0.0264"/>
<site name="sart_r_sart_r-P5" pos="0.0136 -0.081 -0.0026"/>
<site name="semimem_r_semimem_r-P2" pos="-0.029 -0.0417 -0.0196"/>
<site name="SM_at_condyles_r_cylinder_semimem_r_1_sidesite"
pos="-0.0416033 -0.0364739 0.0150787" size="0.0005"/>
<site name="semiten_r_semiten_r-P2" pos="-0.0312 -0.0508 -0.0229"/>
<site name="semiten_r_semiten_r-P3" pos="0.0019 -0.0773 -0.0117"/>
<site name="ST_at_condyles_r_cylinder_semiten_r_1_sidesite"
pos="-0.0469993 -0.0334789 -0.0262674" size="0.0005"/>
<site name="soleus_r_soleus_r-P1" pos="-0.0076 -0.0916 0.0098"/>
<site name="tfl_r_tfl_r-P4" pos="0.0108 -0.041 0.0346"/>
<site name="tibant_r_tibant_r-P1" pos="0.0154 -0.1312 0.0162"/>
<site name="tibant_r_tibant_r-P2" pos="0.0251 -0.1906 0.0128"/>
<site name="tibant_r_tibant_r-P3" pos="0.0233 -0.3659 -0.0132"/>
<site name="tibpost_r_tibpost_r-P1" pos="-0.0041 -0.1304 0.0103"/>
<site name="tibpost_r_tibpost_r-P2" pos="-0.0164 -0.3655 -0.0175"/>
<site name="vasint_r_vasint_r-P5" pos="0.03257 -0.0632 0.00043"/>
<site name="vaslat_r_vaslat_r-P5" pos="0.03254 -0.06338 0.00511"/>
<site name="vasmed_r_vasmed_r-P5" pos="0.0319 -0.06357 -0.00678"/>
<site name="RKJC_marker" pos="0.001731 -0.002389 -0.008452" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RTB1_marker" pos="-0.001662 -0.1565 0.04924" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RTB2_marker" pos="0.03696 -0.2301 -0.003917" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RTB3_marker" pos="0.01138 -0.2952 0.05535" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RLMAL_marker" pos="-0.005 -0.3888 0.053" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RMMAL_marker" pos="0.006 -0.3888 -0.038" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
<site name="R_tibial_plateau_marker" pos="-0.00809 -0.017 -0.001485"
size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<body name="talus_r" pos="-0.01 -0.4 0">
  <inertial pos="0 0 0" mass="0.1" diaginertia="0.001 0.001 0.001"/>
  <joint name="ankle_angle_r" pos="0 0 0" axis="-0.105003 -0.174005
0.979131" range="-0.6981 0.5236"/>
  <geom name="talus_r_geom_1" type="mesh" rgba="1 1 1 1"
mesh="talus_r_geom_1_r_talus"/>
  <site name="RAJC_marker" pos="0 0 0" size="0.01" group="4" rgba="1 0.1
0.5 0.5"/>
  <body name="calcn_r" pos="-0.04877 -0.04195 0.00792">
    <inertial pos="0.1 0.03 0" quat="0 0.707107 0 0.707107" mass="1.25"
diaginertia="0.0041 0.0039 0.0014"/>
```

```xml
<joint name="subtalar_angle_r" pos="0 0 0" axis="0.787215 0.604711 -0.120902" range="-0.3491 0.3491"/>
<geom name="calcn_r_geom_1" type="mesh" rgba="1 1 1 1" mesh="calcn_r_geom_1_r_foot"/>
<site name="edl_r_edl_r-P3" pos="0.0919 0.036 0.0008"/>
<site name="edl_r_edl_r-P4" pos="0.1616 0.0055 0.013"/>
<site name="ehl_r_ehl_r-P4" pos="0.097 0.0389 -0.0211"/>
<site name="ehl_r_ehl_r-P5" pos="0.1293 0.0309 -0.0257"/>
<site name="ehl_r_ehl_r-P6" pos="0.1734 0.0139 -0.028"/>
<site name="fdl_r_fdl_r-P3" pos="0.0436 0.0315 -0.028"/>
<site name="fdl_r_fdl_r-P4" pos="0.0708 0.0176 -0.0263"/>
<site name="fdl_r_fdl_r-P5" pos="0.1658 -0.0081 0.0116"/>
<site name="fhl_r_fhl_r-P3" pos="0.0374 0.0276 -0.0241"/>
<site name="fhl_r_fhl_r-P4" pos="0.1038 0.0068 -0.0256"/>
<site name="fhl_r_fhl_r-P5" pos="0.1726 -0.0053 -0.0269"/>
<site name="gaslat_r_gaslat_r-P2" pos="0.0044 0.031 -0.0053"/>
<site name="gasmed_r_gasmed_r-P2" pos="0.0044 0.031 -0.0053"/>
<site name="perbrev_r_perbrev_r-P4" pos="0.0471 0.027 0.0233"/>
<site name="perbrev_r_perbrev_r-P5" pos="0.0677 0.0219 0.0343"/>
<site name="perlong_r_perlong_r-P4" pos="0.0438 0.023 0.0221"/>
<site name="perlong_r_perlong_r-P5" pos="0.0681 0.0106 0.0284"/>
<site name="perlong_r_perlong_r-P6" pos="0.0852 0.0069 0.0118"/>
<site name="perlong_r_perlong_r-P7" pos="0.1203 0.0085 -0.0184"/>
<site name="soleus_r_soleus_r-P2" pos="0.0044 0.031 -0.0053"/>
<site name="tibant_r_tibant_r-P4" pos="0.1166 0.0178 -0.0305"/>
<site name="tibpost_r_tibpost_r-P3" pos="0.0417 0.0334 -0.0286"/>
<site name="tibpost_r_tibpost_r-P4" pos="0.0772 0.0159 -0.0281"/>
<site name="RCAL_marker" pos="-0.025 0.02 -0.005" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RTOE_marker" pos="0.205 0.02973 -0.03" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RMT5_marker" pos="0.145 0.02491 0.059" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<body name="toes_r" pos="0.1788 -0.002 0.00108">
 <inertial pos="0.0346 0.006 -0.0175" quat="0 0.707107 0 0.707107" mass="0.2166" diaginertia="0.001 0.001 0.001"/>
<joint name="mtp_angle_r" pos="0 0 0" axis="0.581002 2.16001e-06 -0.813902" range="-0.5236 0.5236"/>
<geom name="toes_r_geom_1" type="mesh" rgba="1 1 1 1" mesh="toes_r_geom_1_r_bofoot"/>
<site name="edl_r_edl_r-P5" pos="0.0003 0.0047 0.0153"/>
<site name="edl_r_edl_r-P6" pos="0.0443 -0.0004 0.025"/>
<site name="ehl_r_ehl_r-P7" pos="0.0298 0.0041 -0.0245"/>
<site name="ehl_r_ehl_r-P8" pos="0.0563 0.0034 -0.0186"/>
<site name="fdl_r_fdl_r-P6" pos="-0.0019 -0.0078 0.0147"/>
<site name="fdl_r_fdl_r-P7" pos="0.0285 -0.0071 0.0215"/>
<site name="fdl_r_fdl_r-P8" pos="0.0441 -0.006 0.0242"/>
<site name="fhl_r_fhl_r-P6" pos="0.0155 -0.0064 -0.0265"/>
<site name="fhl_r_fhl_r-P7" pos="0.0562 -0.0102 -0.0181"/>
</body>
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        </body>
      </body>
    </body>
    <body name="patella_r" pos="-0.00809 -0.408 -0.00275">
      <inertial pos="0.0018 0.0264 0" quat="0.5 0.5 0.5 0.5" mass="0.0862"
diaginertia="0.001 0.001 0.001"/>
      <joint name="patellofemoral_r_translation1" pos="0 0 0" axis="1 0 0"
type="slide" range="-0.0227 0.0524" user="0.0524192"/>
      <joint name="patellofemoral_r_translation2" pos="0 0 0" axis="0 1 0"
type="slide" range="-0.0408 -0.0108" user="-0.0108281"/>
      <joint name="patellofemoral_r_translation3" pos="0 0 0" axis="0 0 1"
limited="false" type="slide"/>
      <joint name="patellofemoral_r_rotation1" pos="0 0 0" axis="0 0 1"
range="-1.786 0.001137" user="0.010506"/>
      <geom name="patella_r_geom_1" type="mesh" rgba="1 1 1 1"
mesh="patella_r_geom_1_r_patella"/>
      <site name="recfem_r_recfem_r-P2" pos="0.01 0.049 0.0007"/>
      <site name="recfem_r_recfem_r-P3" pos="0.0121 0.0437 -0.001"/>
      <site name="recfem_r_recfem_r-P4" pos="0.005 0.00247 3e-05"/>
      <site name="vasint_r_vasint_r-P3" pos="0.0058 0.048 -0.0006"/>
      <site name="vasint_r_vasint_r-P4" pos="0.005 0.00247 -0.00039"/>
      <site name="vaslat_r_vaslat_r-P3" pos="0.0103 0.0423 0.0141"/>
      <site name="vaslat_r_vaslat_r-P4" pos="0.005 0.00247 0.00733"/>
      <site name="vasmed_r_vasmed_r-P3" pos="0.0063 0.0445 -0.017"/>
      <site name="vasmed_r_vasmed_r-P4" pos="0.005 0.00247 -0.0085"/>
    </body>
  </body>
  <body name="femur_l" pos="-0.05628 -0.07849 -0.07726">
    <inertial pos="0 -0.17 0" quat="0.5 0.5 -0.5 0.5" mass="9.3014"
diaginertia="0.1412 0.1339 0.0351"/>
    <joint name="hip_flexion_l" pos="0 0 0" axis="0 0 1" range="-0.5236 2.094"/>
    <joint name="hip_adduction_l" pos="0 0 0" axis="-1 0 0" range="-0.8727
0.5236"/>
    <joint name="hip_rotation_l" pos="0 0 0" axis="0 -1 0" range="-0.6981 0.6981"/
>
    <geom name="femur_l_geom_1" type="mesh" rgba="1 1 1 1"
mesh="femur_l_geom_1_l_femur"/>
    <geom name="Gastroc_at_condyles_l_cylinder" size="0.025 0.05" pos="0.005
-0.41 0" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="KnExt_at_fem_l_cylinder" size="0.025 0.05" pos="0.003588
-0.4027 -0.002091" quat="0.999192 0.0311549 -0.0253649 -0.000790882"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AB_at_femshaft_l_cylinder" size="0.0165 0.035" pos="0.01464
-0.1126 -0.02337" quat="0.671205 -0.735393 -0.0628058 0.068812" type="cylinder"
group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AL_at_femshaft_l_cylinder" size="0.0201 0.05" pos="0.03073
-0.2319 -0.01511" quat="0.629109 -0.77432 -0.0430035 0.0529295" type="cylinder"
group="2" rgba="0.19 0.83 0.78 0.2"/>
    <geom name="AMprox_at_femshaft_l_cylinder" size="0.0211 0.035"
pos="0.005183 -0.07289 -0.0254" quat="0.689738 -0.718041 -0.0645399
```

0.0671882" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="AMmid_at_femshaft_l_cylinder" size="0.0214 0.06"
pos="0.02301 -0.1607 -0.02058" quat="0.691136 -0.719496 -0.0472781 0.0492181"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="AMdist_at_femshaft_l_cylinder" size="0.0218 0.1" pos="0.03161
-0.2607 -0.009365" quat="0.652613 -0.751942 -0.0610661 0.0703605"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="AMisch_at_condyles_l_cylinder" size="0.04 0.12"
pos="-0.02265 -0.3768 0.003154" quat="0.638315 -0.734726 0.150602 -0.173349"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="PECT_at_femshaft_l_cylinder" size="0.015 0.025"
pos="0.006086 -0.0845 -0.03044" quat="0.610631 -0.779849 -0.0848995 0.108427"
type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <site name="addbrev_l_addbrev_l-P2" pos="-0.002 -0.118 -0.0249"/>
        <site name="AB_at_femshaft_l_cylinder_addbrev_l_1_sidesite"
pos="-0.00311706 -0.124774 -0.020741" size="0.0005"/>
        <site name="addlong_l_addlong_l-P2" pos="0.01126 -0.23937 -0.01583"/>
        <site name="AL_at_femshaft_l_cylinder_addlong_l_1_sidesite" pos="0.01126
-0.2394 -0.01583" size="0.0005"/>
        <site name="addmagDist_l_addmagDist_l-P2" pos="0.01125 -0.2625 -0.0193"/
>
        <site name="AMdist_at_femshaft_l_cylinder_addmagDist_l_1_sidesite"
pos="0.0108533 -0.272042 -0.0218034" size="0.0005"/>
        <site name="addmagIsch_l_addmagIsch_l-P2" pos="0.00481 -0.38797
0.03273"/>
        <site name="AMisch_at_condyles_l_cylinder_addmagIsch_l_1_sidesite"
pos="0.00481 -0.388 0.03273" size="0.0005"/>
        <site name="addmagMid_l_addmagMid_l-P2" pos="0.00242 -0.1624 -0.02922"/
>
        <site name="AMmid_at_femshaft_l_cylinder_addmagMid_l_1_sidesite"
pos="0.00242 -0.1624 -0.02922" size="0.0005"/>
        <site name="addmagProx_l_addmagProx_l-P2" pos="-0.01527 -0.07886
-0.03202"/>
        <site name="AMprox_at_femshaft_l_cylinder_addmagProx_l_1_sidesite"
pos="-0.0188523 -0.0790318 -0.0306485" size="0.0005"/>
        <site name="bfsh_l_bfsh_l-P1" pos="0.005 -0.2111 -0.0234"/>
        <site name="gaslat_l_gaslat_l-P1" pos="-0.003 -0.3814 -0.0277"/>
        <site name="Gastroc_at_condyles_l_cylinder_gaslat_l_1_sidesite"
pos="-0.0233677 -0.400239 0.00996928" size="0.0005"/>
        <site name="gasmed_l_gasmed_l-P1" pos="0.008 -0.3788 0.0208"/>
        <site name="Gastroc_at_condyles_l_cylinder_gasmed_l_1_sidesite"
pos="-0.024175 -0.403013 0.0181224" size="0.0005"/>
        <site name="glmax1_l_glmax1_l-P3" pos="-0.0444 -0.0326 -0.0302"/>
        <site name="glmax1_l_glmax1_l-P4" pos="-0.0277 -0.0566 -0.047"/>
        <site name="glmax2_l_glmax2_l-P3" pos="-0.045 -0.0584 -0.0252"/>
        <site name="glmax2_l_glmax2_l-P4" pos="-0.0156 -0.1016 -0.0419"/>
        <site name="glmax3_l_glmax3_l-P3" pos="-0.0281 -0.1125 -0.0094"/>
        <site name="glmax3_l_glmax3_l-P4" pos="-0.006 -0.1419 -0.0411"/>
        <site name="glmed1_l_glmed1_l-P2" pos="-0.0218 -0.0117 -0.0555"/>
        <site name="glmed2_l_glmed2_l-P2" pos="-0.0258 -0.0058 -0.0527"/>

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<site name="glmed3_l_glmed3_l-P2" pos="-0.0309 -0.0047 -0.0518"/>
<site name="glmin1_l_glmin1_l-P2" pos="-0.0072 -0.0104 -0.056"/>
<site name="glmin2_l_glmin2_l-P2" pos="-0.0096 -0.0104 -0.056"/>
<site name="glmin3_l_glmin3_l-P2" pos="-0.0135 -0.0083 -0.055"/>
<site name="iliacus_l_iliacus_l-P3" pos="-0.0023 -0.0565 -0.0139"/>
<site name="iliacus_l_iliacus_l-P4" pos="-0.0122 -0.0637 -0.0196"/>
<site name="piri_l_piri_l-P3" pos="-0.0148 -0.0036 -0.0437"/>
<site name="psoas_l_psoas_l-P3" pos="-0.0132 -0.0467 -0.0046"/>
<site name="psoas_l_psoas_l-P4" pos="-0.0235 -0.0524 -0.0088"/>
<site name="KnExt_at_fem_l_cylinder_recfem_l_3_sidesite" pos="0.253588
-0.1527 0.247909" size="0.0005"/>
<site name="sart_l_sart_l-P2" pos="-0.003 -0.3568 0.0421"/>
<site name="tfl_l_tfl_l-P2" pos="0.0294 -0.0995 -0.0597"/>
<site name="tfl_l_tfl_l-P3" pos="0.0107 -0.405 -0.0324"/>
<site name="vasint_l_vasint_l-P1" pos="0.029 -0.1924 -0.031"/>
<site name="vasint_l_vasint_l-P2" pos="0.0335 -0.2084 -0.0285"/>
<site name="KnExt_at_fem_l_cylinder_vasint_l_3_sidesite" pos="0.253588
-0.1527 0.247909" size="0.0005"/>
<site name="vaslat_l_vaslat_l-P1" pos="0.0048 -0.1854 -0.0349"/>
<site name="vaslat_l_vaslat_l-P2" pos="0.0269 -0.2591 -0.0409"/>
<site name="KnExt_at_fem_l_cylinder_vaslat_l_3_sidesite" pos="0.253588
-0.1527 0.247909" size="0.0005"/>
<site name="vasmed_l_vasmed_l-P1" pos="0.014 -0.2099 -0.0188"/>
<site name="vasmed_l_vasmed_l-P2" pos="0.0356 -0.2769 -0.0009"/>
<site name="KnExt_at_fem_l_cylinder_vasmed_l_4_sidesite" pos="-0.007846
-0.4075 0.02075" size="0.0005"/>
<site name="KnExt_at_fem_l_cylinder_vasmed_l_3_sidesite" pos="-0.007846
-0.4075 0.02075" size="0.0005"/>
<site name="LHJC_marker" pos="0 0 0" size="0.01" group="4" rgba="1 0.1 0.5
0.5"/>
<site name="LTH1_marker" pos="0.018 -0.15 -0.064" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="LTH2_marker" pos="0.08 -0.23 -0.0047" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="LTH3_marker" pos="0.01 -0.3 -0.06" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="LLFC_marker" pos="0 -0.404 -0.05" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="LMFC_marker" pos="0 -0.404 0.05" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<body name="tibia_l" pos="-4.6e-07 -0.4044 0.001265">
 <inertial pos="0 -0.1867 0" quat="0.5 0.5 -0.5 0.5" mass="3.7075"
diaginertia="0.0511 0.0504 0.0051"/>
<joint name="walker_knee_l_translation1" pos="0 0 0" axis="-0.124295
0.989762 0.0701573" type="slide" range="0 0.001599" user="9.53733e-08"/>
<joint name="walker_knee_l_translation2" pos="0 0 0" axis="-0.992243
-0.124005 -0.00878938" type="slide" range="-0.006792 0" user="-7.69254e-11"/>
<joint name="knee_angle_l" pos="0 0 0" axis="4.56599e-07 0.0707098
-0.997497" range="0 2.094"/>
<joint name="walker_knee_l_rotation2" pos="0 0 0" axis="-0.992243
```

-0.124005 -0.00878938" range="-0.001678 0.03354" user="-1.47325e-08"/>
        <joint name="walker_knee_l_rotation3" pos="0 0 0" axis="-0.124295 0.989762 0.0701573" range="-0.2628 0" user="-1.08939e-08"/>
        <geom name="tibia_l_geom_1" type="mesh" rgba="1 1 1 1" mesh="tibia_l_geom_1_l_tibia"/>
        <geom name="tibia_l_geom_2" type="mesh" rgba="1 1 1 1" mesh="tibia_l_geom_2_l_fibula"/>
        <geom name="GasLat_at_shank_l_cylinder" size="0.055 0.05" pos="-0.0074 -0.074 0.0033" quat="-0.0297182 -0.737325 -0.65545 -0.160791" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="GasMed_at_shank_l_cylinder" size="0.055 0.05" pos="-0.0074 -0.074 0.0033" quat="0.0738196 -0.735435 -0.67182 -0.0484208" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="GR_at_condyles_l_cylinder" size="0.036 0.05" pos="-0.003 -0.02 0" quat="0.980067 0 0.198669 0" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="SM_at_condyles_l_cylinder" size="0.0352 0.05" pos="-0.001 -0.02 0" quat="0.99875 0 0.0499792 0" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="ST_at_condyles_l_cylinder" size="0.0425 0.05" pos="-0.002 -0.0205 0" quat="0.995004 0 0.0998334 0" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <geom name="BF_at_gastroc_l_cylinder" size="0.03 0.075" pos="-0.058 -0.06 0" type="cylinder" group="2" rgba="0.19 0.83 0.78 0.2"/>
        <site name="GasLat_at_shank_l_sidesite" pos="-0.06099 -0.06623 -0.01096" size="0.0005"/>
        <site name="GasMed_at_shank_l_sidesite" pos="-0.06314 -0.06917 0.005735" size="0.0005"/>
        <site name="bflh_l_bflh_l-P2" pos="-0.0337 -0.035 -0.0253"/>
        <site name="bflh_l_bflh_l-P3" pos="-0.0287 -0.0455 -0.0303"/>
        <site name="bfsh_l_bfsh_l-P2" pos="-0.0301 -0.0419 -0.0318"/>
        <site name="edl_l_edl_l-P1" pos="-0.016 -0.1157 -0.0205"/>
        <site name="edl_l_edl_l-P2" pos="0.0164 -0.376 -0.0112"/>
        <site name="ehl_l_ehl_l-P1" pos="-0.014 -0.155 -0.0189"/>
        <site name="ehl_l_ehl_l-P2" pos="0.0071 -0.2909 -0.0164"/>
        <site name="ehl_l_ehl_l-P3" pos="0.02 -0.3693 0.0028"/>
        <site name="fdl_l_fdl_l-P1" pos="-0.0023 -0.1832 0.0018"/>
        <site name="fdl_l_fdl_l-P2" pos="-0.0176 -0.3645 0.0124"/>
        <site name="fhl_l_fhl_l-P1" pos="-0.031 -0.2163 -0.02"/>
        <site name="fhl_l_fhl_l-P2" pos="-0.0242 -0.3671 0.0076"/>
        <site name="grac_l_grac_l-P2" pos="-0.01842 -0.04755 0.02961"/>
        <site name="grac_l_grac_l-P3" pos="0.00178 -0.06962 0.01573"/>
        <site name="GR_at_condyles_l_cylinder_grac_l_1_sidesite" pos="-0.0386012 -0.0168756 0.0264394" size="0.0005"/>
        <site name="perbrev_l_perbrev_l-P1" pos="-0.0243 -0.2532 -0.0251"/>
        <site name="perbrev_l_perbrev_l-P2" pos="-0.0339 -0.3893 -0.0249"/>
        <site name="perbrev_l_perbrev_l-P3" pos="-0.0285 -0.4004 -0.0255"/>
        <site name="perlong_l_perlong_l-P1" pos="-0.02 -0.1373 -0.0282"/>
        <site name="perlong_l_perlong_l-P2" pos="-0.0317 -0.39 -0.0237"/>
        <site name="perlong_l_perlong_l-P3" pos="-0.0272 -0.4014 -0.024"/>

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<site name="recfem_l_recfem_l-P5" pos="0.0326 -0.06312 0.00047"/>
<site name="sart_l_sart_l-P3" pos="-0.0251 -0.0401 0.0365"/>
<site name="sart_l_sart_l-P4" pos="-0.0159 -0.0599 0.0264"/>
<site name="sart_l_sart_l-P5" pos="0.0136 -0.081 0.0026"/>
<site name="semimem_l_semimem_l-P2" pos="-0.029 -0.0417 0.0196"/>
<site name="SM_at_condyles_l_cylinder_semimem_l_1_sidesite" pos="-0.0390773 -0.0417968 -0.0170819" size="0.0005"/>
<site name="semiten_l_semiten_l-P2" pos="-0.0312 -0.0508 0.0229"/>
<site name="semiten_l_semiten_l-P3" pos="0.0019 -0.0773 0.0117"/>
<site name="ST_at_condyles_l_cylinder_semiten_l_1_sidesite" pos="-0.0439819 -0.0261896 0.0480022" size="0.0005"/>
<site name="soleus_l_soleus_l-P1" pos="-0.0076 -0.0916 -0.0098"/>
<site name="tfl_l_tfl_l-P4" pos="0.0108 -0.041 -0.0346"/>
<site name="tibant_l_tibant_l-P1" pos="0.0154 -0.1312 -0.0162"/>
<site name="tibant_l_tibant_l-P2" pos="0.0251 -0.1906 -0.0128"/>
<site name="tibant_l_tibant_l-P3" pos="0.0233 -0.3659 0.0132"/>
<site name="tibpost_l_tibpost_l-P1" pos="-0.0041 -0.1304 -0.0103"/>
<site name="tibpost_l_tibpost_l-P2" pos="-0.0164 -0.3655 0.0175"/>
<site name="vasint_l_vasint_l-P5" pos="0.03257 -0.0632 -0.00043"/>
<site name="vaslat_l_vaslat_l-P5" pos="0.03254 -0.06338 -0.00511"/>
<site name="vasmed_l_vasmed_l-P5" pos="0.0319 -0.06357 0.00678"/>
<site name="LKJC_marker" pos="0.001731 -0.002389 0.008452" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="LTB1_marker" pos="-0.001662 -0.1565 -0.04924" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="LTB2_marker" pos="0.03696 -0.2301 0.003917" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="LTB3_marker" pos="0.01138 -0.2952 -0.05535" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="LLMAL_marker" pos="-0.005 -0.3888 -0.053" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="LMMAL_marker" pos="0.006 -0.3888 0.038" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="L_tibial_plateau_marker" pos="-0.00809 -0.017 0.001485" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<body name="talus_l" pos="-0.01 -0.4 0">
  <inertial pos="0 0 0" mass="0.1" diaginertia="0.001 0.001 0.001"/>
  <joint name="ankle_angle_l" pos="0 0 0" axis="0.105003 0.174005 0.979131" range="-0.6981 0.5236"/>
  <geom name="talus_l_geom_1" type="mesh" rgba="1 1 1 1" mesh="talus_l_geom_1_l_talus"/>
  <site name="LAJC_marker" pos="0 0 0" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
  <body name="calcn_l" pos="-0.04877 -0.04195 -0.00792">
    <inertial pos="0.1 0.03 0" quat="0 0.707107 0 0.707107" mass="1.25" diaginertia="0.0041 0.0039 0.0014"/>
    <joint name="subtalar_angle_l" pos="0 0 0" axis="-0.787215 -0.604711 -0.120902" range="-0.3491 0.3491"/>
    <geom name="calcn_l_geom_1" type="mesh" rgba="1 1 1 1" mesh="calcn_l_geom_1_l_foot"/>
```

```xml
<site name="edl_l_edl_l-P3" pos="0.0919 0.036 -0.0008"/>
<site name="edl_l_edl_l-P4" pos="0.1616 0.0055 -0.013"/>
<site name="ehl_l_ehl_l-P4" pos="0.097 0.0389 0.0211"/>
<site name="ehl_l_ehl_l-P5" pos="0.1293 0.0309 0.0257"/>
<site name="ehl_l_ehl_l-P6" pos="0.1734 0.0139 0.028"/>
<site name="fdl_l_fdl_l-P3" pos="0.0436 0.0315 0.028"/>
<site name="fdl_l_fdl_l-P4" pos="0.0708 0.0176 0.0263"/>
<site name="fdl_l_fdl_l-P5" pos="0.1658 -0.0081 -0.0116"/>
<site name="fhl_l_fhl_l-P3" pos="0.0374 0.0276 0.0241"/>
<site name="fhl_l_fhl_l-P4" pos="0.1038 0.0068 0.0256"/>
<site name="fhl_l_fhl_l-P5" pos="0.1726 -0.0053 0.0269"/>
<site name="gaslat_l_gaslat_l-P2" pos="0.0044 0.031 0.0053"/>
<site name="gasmed_l_gasmed_l-P2" pos="0.0044 0.031 0.0053"/>
<site name="perbrev_l_perbrev_l-P4" pos="0.0471 0.027 -0.0233"/>
<site name="perbrev_l_perbrev_l-P5" pos="0.0677 0.0219 -0.0343"/>
<site name="perlong_l_perlong_l-P4" pos="0.0438 0.023 -0.0221"/>
<site name="perlong_l_perlong_l-P5" pos="0.0681 0.0106 -0.0284"/>
<site name="perlong_l_perlong_l-P6" pos="0.0852 0.0069 -0.0118"/>
<site name="perlong_l_perlong_l-P7" pos="0.1203 0.0085 0.0184"/>
<site name="soleus_l_soleus_l-P2" pos="0.0044 0.031 0.0053"/>
<site name="tibant_l_tibant_l-P4" pos="0.1166 0.0178 0.0305"/>
<site name="tibpost_l_tibpost_l-P3" pos="0.0417 0.0334 0.0286"/>
<site name="tibpost_l_tibpost_l-P4" pos="0.0772 0.0159 0.0281"/>
<site name="LCAL_marker" pos="-0.025 0.02 0.005" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="LTOE_marker" pos="0.205 0.02973 0.03" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="LMT5_marker" pos="0.145 0.02491 -0.059" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<body name="toes_l" pos="0.1788 -0.002 -0.00108">
  <inertial pos="0.0346 0.006 0.0175" quat="0 0.707107 0 0.707107" mass="0.2166" diaginertia="0.001 0.001 0.001"/>
  <joint name="mtp_angle_l" pos="0 0 0" axis="-0.581002 2.16001e-06 -0.813902" range="-0.5236 0.5236"/>
  <geom name="toes_l_geom_1" type="mesh" rgba="1 1 1 1" mesh="toes_l_geom_1_l_bofoot"/>
  <site name="edl_l_edl_l-P5" pos="0.0003 0.0047 -0.0153"/>
  <site name="edl_l_edl_l-P6" pos="0.0443 -0.0004 -0.025"/>
  <site name="ehl_l_ehl_l-P7" pos="0.0298 0.0041 0.0245"/>
  <site name="ehl_l_ehl_l-P8" pos="0.0563 0.0034 0.0186"/>
  <site name="fdl_l_fdl_l-P6" pos="-0.0019 -0.0078 -0.0147"/>
  <site name="fdl_l_fdl_l-P7" pos="0.0285 -0.0071 -0.0215"/>
  <site name="fdl_l_fdl_l-P8" pos="0.0441 -0.006 -0.0242"/>
  <site name="fhl_l_fhl_l-P6" pos="0.0155 -0.0064 0.0265"/>
  <site name="fhl_l_fhl_l-P7" pos="0.0562 -0.0102 0.0181"/>
</body>
    </body>
   </body>
  </body>
  <body name="patella_l" pos="-0.00809 -0.408 0.00275">
```

```xml
<inertial pos="0.0018 0.0264 0" quat="0.5 0.5 0.5 0.5" mass="0.0862"
diaginertia="0.001 0.001 0.001"/>
<joint name="patellofemoral_l_translation1" pos="0 0 0" axis="1 0 0"
type="slide" range="-0.0227 0.0524" user="0.0524192"/>
<joint name="patellofemoral_l_translation2" pos="0 0 0" axis="0 1 0"
type="slide" range="-0.0408 -0.0108" user="-0.0108281"/>
<joint name="patellofemoral_l_translation3" pos="0 0 0" axis="0 0 1"
limited="false" type="slide"/>
<joint name="patellofemoral_l_rotation1" pos="0 0 0" axis="0 0 1"
range="-1.786 0.001137" user="0.010506"/>
<geom name="patella_l_geom_1" type="mesh" rgba="1 1 1 1"
mesh="patella_l_geom_1_l_patella"/>
<site name="recfem_l_recfem_l-P2" pos="0.01 0.049 -0.0007"/>
<site name="recfem_l_recfem_l-P3" pos="0.0121 0.0437 0.001"/>
<site name="recfem_l_recfem_l-P4" pos="0.005 0.00247 -3e-05"/>
<site name="vasint_l_vasint_l-P3" pos="0.0058 0.048 0.0006"/>
<site name="vasint_l_vasint_l-P4" pos="0.005 0.00247 0.00039"/>
<site name="vaslat_l_vaslat_l-P3" pos="0.0103 0.0423 -0.0141"/>
<site name="vaslat_l_vaslat_l-P4" pos="0.005 0.00247 -0.00733"/>
<site name="vasmed_l_vasmed_l-P3" pos="0.0063 0.0445 0.017"/>
<site name="vasmed_l_vasmed_l-P4" pos="0.005 0.00247 0.0085"/>
</body>
</body>
<body name="torso" pos="-0.1007 0.0815 0">
<inertial pos="-0.03 0.32 0" quat="0.707107 0.707107 0 0" mass="26.8266"
diaginertia="1.4745 1.4314 0.7555"/>
<joint name="lumbar_extension" pos="0 0 0" axis="0 0 1" range="-1.571
1.571"/>
<joint name="lumbar_bending" pos="0 0 0" axis="1 0 0" range="-1.571 1.571"/>
<joint name="lumbar_rotation" pos="0 0 0" axis="0 1 0" range="-1.571 1.571"/>
<geom name="torso_geom_1" type="mesh" rgba="1 1 1 1"
mesh="torso_geom_1_hat_spine"/>
<geom name="torso_geom_2" type="mesh" rgba="1 1 1 1"
mesh="torso_geom_2_hat_jaw"/>
<geom name="torso_geom_3" type="mesh" rgba="1 1 1 1"
mesh="torso_geom_3_hat_skull"/>
<geom name="torso_geom_4" type="mesh" rgba="1 1 1 1"
mesh="torso_geom_4_hat_ribs_scap"/>
<site name="RACR_marker" pos="-0.003 0.425 0.13" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="LACR_marker" pos="-0.003 0.425 -0.13" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="C7_marker" pos="-0.085 0.435 0.001654" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="CLAV_marker" pos="0.04 0.38 0.017" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="RASH_marker" pos="0.05 0.3715 0.17" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
<site name="RPSH_marker" pos="-0.05 0.3715 0.17" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
```

```xml
<site name="LASH_marker" pos="0.05 0.3715 -0.17" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="LPSH_marker" pos="-0.058 0.3715 -0.17" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<body name="humerus_r" pos="0.003155 0.3715 0.17">
<inertial pos="0 -0.164502 0" quat="0.5 0.5 -0.5 0.5" mass="2.0325" diaginertia="0.013409 0.011946 0.004121"/>
<joint name="arm_flex_r" pos="0 0 0" axis="0 0 1" range="-1.571 1.571"/>
<joint name="arm_add_r" pos="0 0 0" axis="1 0 0" range="-2.094 1.571"/>
<joint name="arm_rot_r" pos="0 0 0" axis="0 1 0" range="-1.571 1.571"/>
<geom name="humerus_r_geom_1" type="mesh" rgba="1 1 1 1" mesh="humerus_r_geom_1_humerus_rv"/>
<site name="RSJC_marker" pos="0 0 0" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RUA1_marker" pos="0 -0.05 0.02" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RUA2_marker" pos="0 -0.2 0.02" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RUA3_marker" pos="0.03 -0.13 0.02" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RLEL_marker" pos="0.015 -0.28 0.04" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RMEL_marker" pos="0.00225 -0.286 -0.046" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<body name="ulna_r" pos="0.01314 -0.2863 -0.009595">
<inertial pos="0 -0.120525 0" quat="0.5 0.5 -0.5 0.5" mass="0.6075" diaginertia="0.003213 0.002962 0.001"/>
<joint name="elbow_flex_r" pos="0 0 0" axis="0.225994 0.0222694 0.973874" range="0 2.618"/>
<geom name="ulna_r_geom_1" type="mesh" rgba="1 1 1 1" mesh="ulna_r_geom_1_ulna_rv"/>
<site name="RFAsuperior_marker" pos="0.004605 -0.08006 0.04532" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="REJC_marker" pos="0 0 0" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<body name="radius_r" pos="-0.006727 -0.01301 0.02608">
<inertial pos="0 -0.120525 0" quat="0.5 0.5 -0.5 0.5" mass="0.6075" diaginertia="0.003213 0.002962 0.001"/>
<joint name="pro_sup_r" pos="0 0 0" axis="0.0564004 0.998406 0.00195301" range="0 1.571"/>
<geom name="radius_r_geom_1" type="mesh" rgba="1 1 1 1" mesh="radius_r_geom_1_radius_rv"/>
<site name="RFAradius_marker" pos="0.0005 -0.225 0.05" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<site name="RFAulna_marker" pos="-0.022 -0.225 -0.022" size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
<body name="hand_r" pos="-0.008797 -0.2358 0.01361">
<inertial pos="0 -0.068095 0" quat="0.5 0.5 -0.5 0.5" mass="0.4575" diaginertia="0.00134 0.001 0.001"/>
<joint name="wrist_flex_r" pos="0 0 0" axis="-3.673e-06 3.673e-06 1"
```

```xml
range="-1.222 1.222"/>
        <joint name="wrist_dev_r" pos="0 0 0" axis="1 1.349e-11 3.673e-06"
range="-0.4363 0.6109"/>
        <geom name="hand_r_geom_1" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_1_pisiform_rvs"/>
        <geom name="hand_r_geom_2" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_2_lunate_rvs"/>
        <geom name="hand_r_geom_3" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_3_scaphoid_rvs"/>
        <geom name="hand_r_geom_4" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_4_triquetrum_rvs"/>
        <geom name="hand_r_geom_5" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_5_hamate_rvs"/>
        <geom name="hand_r_geom_6" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_6_capitate_rvs"/>
        <geom name="hand_r_geom_7" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_7_trapezoid_rvs"/>
        <geom name="hand_r_geom_8" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_8_trapezium_rvs"/>
        <geom name="hand_r_geom_9" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_9_metacarpal2_rvs"/>
        <geom name="hand_r_geom_10" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_10_index_proximal_rvs"/>
        <geom name="hand_r_geom_11" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_11_index_medial_rvs"/>
        <geom name="hand_r_geom_12" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_12_index_distal_rvs"/>
        <geom name="hand_r_geom_13" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_13_metacarpal3_rvs"/>
        <geom name="hand_r_geom_14" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_14_middle_proximal_rvs"/>
        <geom name="hand_r_geom_15" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_15_middle_medial_rvs"/>
        <geom name="hand_r_geom_16" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_16_middle_distal_rvs"/>
        <geom name="hand_r_geom_17" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_17_metacarpal4_rvs"/>
        <geom name="hand_r_geom_18" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_18_ring_proximal_rvs"/>
        <geom name="hand_r_geom_19" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_19_ring_medial_rvs"/>
        <geom name="hand_r_geom_20" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_20_ring_distal_rvs"/>
        <geom name="hand_r_geom_21" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_21_metacarpal5_rvs"/>
        <geom name="hand_r_geom_22" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_22_little_proximal_rvs"/>
        <geom name="hand_r_geom_23" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_23_little_medial_rvs"/>
        <geom name="hand_r_geom_24" type="mesh" rgba="1 1 1 1"
```

```xml
mesh="hand_r_geom_24_little_distal_rvs"/>
          <geom name="hand_r_geom_25" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_25_metacarpal1_rvs"/>
          <geom name="hand_r_geom_26" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_26_thumb_proximal_rvs"/>
          <geom name="hand_r_geom_27" type="mesh" rgba="1 1 1 1"
mesh="hand_r_geom_27_thumb_distal_rvs"/>
      </body>
     </body>
    </body>
   </body>
   <body name="humerus_l" pos="0.003155 0.3715 -0.17">
    <inertial pos="0 -0.164502 0" quat="0.5 0.5 -0.5 0.5" mass="2.0325"
diaginertia="0.013409 0.011946 0.004121"/>
      <joint name="arm_flex_l" pos="0 0 0" axis="0 0 1" range="-1.571 1.571"/>
      <joint name="arm_add_l" pos="0 0 0" axis="-1 0 0" range="-2.094 1.571"/>
      <joint name="arm_rot_l" pos="0 0 0" axis="0 -1 0" range="-1.571 1.571"/>
      <geom name="humerus_l_geom_1" type="mesh" rgba="1 1 1 1"
mesh="humerus_l_geom_1_humerus_lv"/>
      <site name="LSJC_marker" pos="0 0 0" size="0.01" group="4" rgba="1 0.1
0.5 0.5"/>
      <site name="LUA1_marker" pos="0 -0.05 -0.02" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
      <site name="LUA2_marker" pos="0 -0.2 -0.02" size="0.01" group="4" rgba="1
0.1 0.5 0.5"/>
      <site name="LUA3_marker" pos="0.03 -0.13 -0.02" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
      <site name="LLEL_marker" pos="0.015 -0.28 -0.04" size="0.01" group="4"
rgba="1 0.1 0.5 0.5"/>
      <site name="LMEL_marker" pos="0.00225 -0.286 0.046" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
      <body name="ulna_l" pos="0.01314 -0.2863 0.009595">
       <inertial pos="0 -0.120525 0" quat="0.5 0.5 -0.5 0.5" mass="0.6075"
diaginertia="0.003213 0.002962 0.001"/>
        <joint name="elbow_flex_l" pos="0 0 0" axis="-0.225994 -0.0222694
0.973874" range="0 2.618"/>
        <geom name="ulna_l_geom_1" type="mesh" rgba="1 1 1 1"
mesh="ulna_l_geom_1_ulna_lv"/>
        <site name="LFAsuperior_marker" pos="0.004605 -0.08006 -0.04532"
size="0.01" group="4" rgba="1 0.1 0.5 0.5"/>
        <site name="LEJC_marker" pos="0 0 0" size="0.01" group="4" rgba="1 0.1
0.5 0.5"/>
        <body name="radius_l" pos="-0.006727 -0.01301 -0.02608">
         <inertial pos="0 -0.120525 0" quat="0.5 0.5 -0.5 0.5" mass="0.6075"
diaginertia="0.003213 0.002962 0.001"/>
          <joint name="pro_sup_l" pos="0 0 0" axis="-0.0564004 -0.998406
0.00195301" range="0 1.571"/>
          <geom name="radius_l_geom_1" type="mesh" rgba="1 1 1 1"
mesh="radius_l_geom_1_radius_lv"/>
          <site name="LFAradius_marker" pos="0.0005 -0.225 -0.05" size="0.01"
```

```xml
group="4" rgba="1 0.1 0.5 0.5"/>
        <site name="LFAulna_marker" pos="-0.022 -0.225 0.022" size="0.01"
group="4" rgba="1 0.1 0.5 0.5"/>
        <body name="hand_l" pos="-0.008797 -0.2358 -0.01361">
        <inertial pos="0 -0.068095 0" quat="0.5 0.5 -0.5 0.5" mass="0.4575"
diaginertia="0.00134 0.001 0.001"/>
        <joint name="wrist_flex_l" pos="0 0 0" axis="-3.673e-06 -3.673e-06 1"
range="-1.222 1.222"/>
        <joint name="wrist_dev_l" pos="0 0 0" axis="-1 1.349e-11 -3.673e-06"
range="-0.4363 0.6109"/>
        <geom name="hand_l_geom_1" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_1_pisiform_lvs"/>
        <geom name="hand_l_geom_2" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_2_lunate_lvs"/>
        <geom name="hand_l_geom_3" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_3_scaphoid_lvs"/>
        <geom name="hand_l_geom_4" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_4_triquetrum_lvs"/>
        <geom name="hand_l_geom_5" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_5_hamate_lvs"/>
        <geom name="hand_l_geom_6" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_6_capitate_lvs"/>
        <geom name="hand_l_geom_7" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_7_trapezoid_lvs"/>
        <geom name="hand_l_geom_8" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_8_trapezium_lvs"/>
        <geom name="hand_l_geom_9" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_9_metacarpal2_lvs"/>
        <geom name="hand_l_geom_10" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_10_index_proximal_lvs"/>
        <geom name="hand_l_geom_11" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_11_index_medial_lvs"/>
        <geom name="hand_l_geom_12" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_12_index_distal_lvs"/>
        <geom name="hand_l_geom_13" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_13_metacarpal3_lvs"/>
        <geom name="hand_l_geom_14" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_14_middle_proximal_lvs"/>
        <geom name="hand_l_geom_15" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_15_middle_medial_lvs"/>
        <geom name="hand_l_geom_16" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_16_middle_distal_lvs"/>
        <geom name="hand_l_geom_17" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_17_metacarpal4_lvs"/>
        <geom name="hand_l_geom_18" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_18_ring_proximal_lvs"/>
        <geom name="hand_l_geom_19" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_19_ring_medial_lvs"/>
        <geom name="hand_l_geom_20" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_20_ring_distal_lvs"/>
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```xml
        <geom name="hand_l_geom_21" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_21_metacarpal5_lvs"/>
        <geom name="hand_l_geom_22" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_22_little_proximal_lvs"/>
        <geom name="hand_l_geom_23" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_23_little_medial_lvs"/>
        <geom name="hand_l_geom_24" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_24_little_distal_lvs"/>
        <geom name="hand_l_geom_25" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_25_metacarpal1_lvs"/>
        <geom name="hand_l_geom_26" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_26_thumb_proximal_lvs"/>
        <geom name="hand_l_geom_27" type="mesh" rgba="1 1 1 1"
mesh="hand_l_geom_27_thumb_distal_lvs"/>
      </body>
     </body>
    </body>
   </body>
  </body>
 </body>
 </worldbody>
 <contact>
  <pair geom1="ground-plane" geom2="pelvis_geom_1"/>
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  <pair geom1="ground-plane" geom2="pelvis_geom_3"/>
  <pair geom1="ground-plane" geom2="femur_r_geom_1"/>
  <pair geom1="ground-plane" geom2="tibia_r_geom_1"/>
  <pair geom1="ground-plane" geom2="tibia_r_geom_2"/>
  <pair geom1="ground-plane" geom2="talus_r_geom_1"/>
  <pair geom1="ground-plane" geom2="calcn_r_geom_1"/>
  <pair geom1="ground-plane" geom2="toes_r_geom_1"/>
  <pair geom1="ground-plane" geom2="patella_r_geom_1"/>
  <pair geom1="ground-plane" geom2="femur_l_geom_1"/>
  <pair geom1="ground-plane" geom2="tibia_l_geom_1"/>
  <pair geom1="ground-plane" geom2="tibia_l_geom_2"/>
  <pair geom1="ground-plane" geom2="talus_l_geom_1"/>
  <pair geom1="ground-plane" geom2="calcn_l_geom_1"/>
  <pair geom1="ground-plane" geom2="toes_l_geom_1"/>
  <pair geom1="ground-plane" geom2="patella_l_geom_1"/>
  <pair geom1="ground-plane" geom2="torso_geom_1"/>
  <pair geom1="ground-plane" geom2="torso_geom_2"/>
  <pair geom1="ground-plane" geom2="torso_geom_3"/>
  <pair geom1="ground-plane" geom2="torso_geom_4"/>
  <pair geom1="ground-plane" geom2="humerus_r_geom_1"/>
  <pair geom1="ground-plane" geom2="ulna_r_geom_1"/>
  <pair geom1="ground-plane" geom2="radius_r_geom_1"/>
  <pair geom1="ground-plane" geom2="hand_r_geom_1"/>
  <pair geom1="ground-plane" geom2="hand_r_geom_2"/>
  <pair geom1="ground-plane" geom2="hand_r_geom_3"/>
  <pair geom1="ground-plane" geom2="hand_r_geom_4"/>
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```xml
<pair geom1="ground-plane" geom2="hand_r_geom_5"/>
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<pair geom1="ground-plane" geom2="hand_r_geom_8"/>
<pair geom1="ground-plane" geom2="hand_r_geom_9"/>
<pair geom1="ground-plane" geom2="hand_r_geom_10"/>
<pair geom1="ground-plane" geom2="hand_r_geom_11"/>
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<pair geom1="ground-plane" geom2="hand_r_geom_14"/>
<pair geom1="ground-plane" geom2="hand_r_geom_15"/>
<pair geom1="ground-plane" geom2="hand_r_geom_16"/>
<pair geom1="ground-plane" geom2="hand_r_geom_17"/>
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<pair geom1="ground-plane" geom2="hand_r_geom_19"/>
<pair geom1="ground-plane" geom2="hand_r_geom_20"/>
<pair geom1="ground-plane" geom2="hand_r_geom_21"/>
<pair geom1="ground-plane" geom2="hand_r_geom_22"/>
<pair geom1="ground-plane" geom2="hand_r_geom_23"/>
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<pair geom1="ground-plane" geom2="hand_r_geom_25"/>
<pair geom1="ground-plane" geom2="hand_r_geom_26"/>
<pair geom1="ground-plane" geom2="hand_r_geom_27"/>
<pair geom1="ground-plane" geom2="humerus_l_geom_1"/>
<pair geom1="ground-plane" geom2="ulna_l_geom_1"/>
<pair geom1="ground-plane" geom2="radius_l_geom_1"/>
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<pair geom1="ground-plane" geom2="hand_l_geom_22"/>
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<pair geom1="ground-plane" geom2="hand_l_geom_24"/>
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```xml
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      <pair geom1="ground-plane" geom2="hand_l_geom_26"/>
      <pair geom1="ground-plane" geom2="hand_l_geom_27"/>
  </contact>
  <equality>
    <joint joint1="walker_knee_r_translation1" joint2="knee_angle_r"
polycoef="9.537e-08 0.003129 -0.002308 0.0005616 5.684e-07" solimp="0.9999
0.9999 0.001 0.5 2"/>
    <joint joint1="walker_knee_r_translation2" joint2="knee_angle_r"
polycoef="7.693e-11 0.00588 -0.001256 -2.618e-06 6.244e-07" solimp="0.9999
0.9999 0.001 0.5 2"/>
    <joint joint1="walker_knee_r_rotation2" joint2="knee_angle_r"
polycoef="-1.473e-08 0.0791 -0.03285 -0.02522 0.01083" solimp="0.9999 0.9999
0.001 0.5 2"/>
    <joint joint1="walker_knee_r_rotation3" joint2="knee_angle_r"
polycoef="1.089e-08 0.3695 -0.1695 0.02516 3.505e-07" solimp="0.9999 0.9999
0.001 0.5 2"/>
    <joint name="subtalar_angle_r_locked" joint1="subtalar_angle_r" polycoef="0 0 0
0 0" solimp="0.9999 0.9999 0.001 0.5 2"/>
    <joint name="mtp_angle_r_locked" joint1="mtp_angle_r" polycoef="0 0 0 0 0"
solimp="0.9999 0.9999 0.001 0.5 2"/>
    <joint joint1="patellofemoral_r_translation1" joint2="knee_angle_r"
polycoef="0.05242 -0.01502 -0.03405 0.01334 -0.0008792" solimp="0.9999 0.9999
0.001 0.5 2"/>
    <joint joint1="patellofemoral_r_translation2" joint2="knee_angle_r"
polycoef="-0.01083 -0.04878 0.009276 0.01317 -0.003497" solimp="0.9999 0.9999
0.001 0.5 2"/>
    <joint joint1="patellofemoral_r_rotation1" joint2="knee_angle_r"
polycoef="0.01051 0.02476 -1.316 0.7163 -0.1383" solimp="0.9999 0.9999 0.001
0.5 2"/>
    <joint name="patellofemoral_r_translation3_locked"
joint1="patellofemoral_r_translation3" polycoef="0.00275 0 0 0 0" solimp="0.9999
0.9999 0.001 0.5 2"/>
    <joint joint1="walker_knee_l_translation1" joint2="knee_angle_l"
polycoef="9.537e-08 0.003129 -0.002308 0.0005616 5.684e-07" solimp="0.9999
0.9999 0.001 0.5 2"/>
    <joint joint1="walker_knee_l_translation2" joint2="knee_angle_l"
polycoef="-7.693e-11 -0.00588 0.001256 2.618e-06 -6.244e-07" solimp="0.9999
0.9999 0.001 0.5 2"/>
    <joint joint1="walker_knee_l_rotation2" joint2="knee_angle_l"
polycoef="-1.473e-08 0.0791 -0.03285 -0.02522 0.01083" solimp="0.9999 0.9999
0.001 0.5 2"/>
    <joint joint1="walker_knee_l_rotation3" joint2="knee_angle_l"
polycoef="-1.089e-08 -0.3695 0.1695 -0.02516 -3.505e-07" solimp="0.9999 0.9999
0.001 0.5 2"/>
    <joint name="subtalar_angle_l_locked" joint1="subtalar_angle_l" polycoef="0 0 0
0 0" solimp="0.9999 0.9999 0.001 0.5 2"/>
    <joint name="mtp_angle_l_locked" joint1="mtp_angle_l" polycoef="0 0 0 0 0"
solimp="0.9999 0.9999 0.001 0.5 2"/>
    <joint joint1="patellofemoral_l_translation1" joint2="knee_angle_l"
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```xml
          polycoef="0.05242 -0.01502 -0.03405 0.01334 -0.0008792" solimp="0.9999 0.9999
0.001 0.5 2"/>
    <joint joint1="patellofemoral_l_translation2" joint2="knee_angle_l"
polycoef="-0.01083 -0.04878 0.009276 0.01317 -0.003497" solimp="0.9999 0.9999
0.001 0.5 2"/>
    <joint joint1="patellofemoral_l_rotation1" joint2="knee_angle_l" polycoef="0.01051
0.02476 -1.316 0.7163 -0.1383" solimp="0.9999 0.9999 0.001 0.5 2"/>
    <joint name="patellofemoral_l_translation3_locked"
joint1="patellofemoral_l_translation3" polycoef="-0.00275 0 0 0 0" solimp="0.9999
0.9999 0.001 0.5 2"/>
    <joint name="wrist_flex_r_locked" joint1="wrist_flex_r" polycoef="0 0 0 0 0"
solimp="0.9999 0.9999 0.001 0.5 2"/>
    <joint name="wrist_dev_r_locked" joint1="wrist_dev_r" polycoef="0 0 0 0 0"
solimp="0.9999 0.9999 0.001 0.5 2"/>
    <joint name="wrist_flex_l_locked" joint1="wrist_flex_l" polycoef="0 0 0 0 0"
solimp="0.9999 0.9999 0.001 0.5 2"/>
    <joint name="wrist_dev_l_locked" joint1="wrist_dev_l" polycoef="0 0 0 0 0"
solimp="0.9999 0.9999 0.001 0.5 2"/>
  </equality>
  <tendon>
    <spatial name="addbrev_r_tendon">
      <site site="addbrev_r_addbrev_r-P1"/>
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sidesite="AB_at_femshaft_r_cylinder_addbrev_r_1_sidesite"/>
      <site site="addbrev_r_addbrev_r-P2"/>
    </spatial>
    <spatial name="addlong_r_tendon">
      <site site="addlong_r_addlong_r-P1"/>
      <geom geom="AL_at_femshaft_r_cylinder"
sidesite="AL_at_femshaft_r_cylinder_addlong_r_1_sidesite"/>
      <site site="addlong_r_addlong_r-P2"/>
    </spatial>
    <spatial name="addmagDist_r_tendon">
      <site site="addmagDist_r_addmagDist_r-P1"/>
      <geom geom="AMdist_at_femshaft_r_cylinder"
sidesite="AMdist_at_femshaft_r_cylinder_addmagDist_r_1_sidesite"/>
      <site site="addmagDist_r_addmagDist_r-P2"/>
    </spatial>
    <spatial name="addmagIsch_r_tendon">
      <site site="addmagIsch_r_addmagIsch_r-P1"/>
      <geom geom="AMisch_at_condyles_r_cylinder"
sidesite="AMisch_at_condyles_r_cylinder_addmagIsch_r_1_sidesite"/>
      <site site="addmagIsch_r_addmagIsch_r-P2"/>
    </spatial>
    <spatial name="addmagMid_r_tendon">
      <site site="addmagMid_r_addmagMid_r-P1"/>
      <geom geom="AMmid_at_femshaft_r_cylinder"
sidesite="AMmid_at_femshaft_r_cylinder_addmagMid_r_1_sidesite"/>
      <site site="addmagMid_r_addmagMid_r-P2"/>
    </spatial>
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```xml
<spatial name="addmagProx_r_tendon">
  <site site="addmagProx_r_addmagProx_r-P1"/>
  <geom geom="AMprox_at_femshaft_r_cylinder"
sidesite="AMprox_at_femshaft_r_cylinder_addmagProx_r_1_sidesite"/>
  <site site="addmagProx_r_addmagProx_r-P2"/>
</spatial>
<spatial name="bflh_r_tendon">
  <site site="bflh_r_bflh_r-P1"/>
  <site site="bflh_r_bflh_r-P2"/>
  <site site="bflh_r_bflh_r-P3"/>
</spatial>
<spatial name="bfsh_r_tendon">
  <site site="bfsh_r_bfsh_r-P1"/>
  <site site="bfsh_r_bfsh_r-P2"/>
</spatial>
<spatial name="edl_r_tendon">
  <site site="edl_r_edl_r-P1"/>
  <site site="edl_r_edl_r-P2"/>
  <site site="edl_r_edl_r-P3"/>
  <site site="edl_r_edl_r-P4"/>
  <site site="edl_r_edl_r-P5"/>
  <site site="edl_r_edl_r-P6"/>
</spatial>
<spatial name="ehl_r_tendon">
  <site site="ehl_r_ehl_r-P1"/>
  <site site="ehl_r_ehl_r-P2"/>
  <site site="ehl_r_ehl_r-P3"/>
  <site site="ehl_r_ehl_r-P4"/>
  <site site="ehl_r_ehl_r-P5"/>
  <site site="ehl_r_ehl_r-P6"/>
  <site site="ehl_r_ehl_r-P7"/>
  <site site="ehl_r_ehl_r-P8"/>
</spatial>
<spatial name="fdl_r_tendon">
  <site site="fdl_r_fdl_r-P1"/>
  <site site="fdl_r_fdl_r-P2"/>
  <site site="fdl_r_fdl_r-P3"/>
  <site site="fdl_r_fdl_r-P4"/>
  <site site="fdl_r_fdl_r-P5"/>
  <site site="fdl_r_fdl_r-P6"/>
  <site site="fdl_r_fdl_r-P7"/>
  <site site="fdl_r_fdl_r-P8"/>
</spatial>
<spatial name="fhl_r_tendon">
  <site site="fhl_r_fhl_r-P1"/>
  <site site="fhl_r_fhl_r-P2"/>
  <site site="fhl_r_fhl_r-P3"/>
  <site site="fhl_r_fhl_r-P4"/>
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  <site site="fhl_r_fhl_r-P6"/>
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```xml
        <site site="fhl_r_fhl_r-P7"/>
      </spatial>
      <spatial name="gaslat_r_tendon">
        <site site="gaslat_r_gaslat_r-P1"/>
        <geom geom="Gastroc_at_condyles_r_cylinder"
sidesite="Gastroc_at_condyles_r_cylinder_gaslat_r_1_sidesite"/>
        <site site="gaslat_r_gaslat_r-P2"/>
      </spatial>
      <spatial name="gasmed_r_tendon">
        <site site="gasmed_r_gasmed_r-P1"/>
        <geom geom="Gastroc_at_condyles_r_cylinder"
sidesite="Gastroc_at_condyles_r_cylinder_gasmed_r_1_sidesite"/>
        <site site="gasmed_r_gasmed_r-P2"/>
      </spatial>
      <spatial name="glmax1_r_tendon">
        <site site="glmax1_r_glmax1_r-P1"/>
        <site site="glmax1_r_glmax1_r-P2"/>
        <geom geom="Gmax1_at_pelvis_r_cylinder"
sidesite="Gmax1_at_pelvis_r_cylinder_glmax1_r_2_sidesite"/>
        <site site="glmax1_r_glmax1_r-P3"/>
        <site site="glmax1_r_glmax1_r-P4"/>
      </spatial>
      <spatial name="glmax2_r_tendon">
        <site site="glmax2_r_glmax2_r-P1"/>
        <site site="glmax2_r_glmax2_r-P2"/>
        <geom geom="Gmax2_at_pelvis_r_cylinder"
sidesite="Gmax2_at_pelvis_r_cylinder_glmax2_r_2_sidesite"/>
        <site site="glmax2_r_glmax2_r-P3"/>
        <site site="glmax2_r_glmax2_r-P4"/>
      </spatial>
      <spatial name="glmax3_r_tendon">
        <site site="glmax3_r_glmax3_r-P1"/>
        <geom geom="Gmax3_at_pelvis_r_cylinder"
sidesite="Gmax3_at_pelvis_r_cylinder_glmax3_r_1_sidesite"/>
        <site site="glmax3_r_glmax3_r-P2"/>
        <site site="glmax3_r_glmax3_r-P3"/>
        <site site="glmax3_r_glmax3_r-P4"/>
      </spatial>
      <spatial name="glmed1_r_tendon">
        <site site="glmed1_r_glmed1_r-P1"/>
        <site site="glmed1_r_glmed1_r-P2"/>
      </spatial>
      <spatial name="glmed2_r_tendon">
        <site site="glmed2_r_glmed2_r-P1"/>
        <site site="glmed2_r_glmed2_r-P2"/>
      </spatial>
      <spatial name="glmed3_r_tendon">
        <site site="glmed3_r_glmed3_r-P1"/>
        <site site="glmed3_r_glmed3_r-P2"/>
      </spatial>
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```xml
<spatial name="glmin1_r_tendon">
  <site site="glmin1_r_glmin1_r-P1"/>
  <site site="glmin1_r_glmin1_r-P2"/>
</spatial>
<spatial name="glmin2_r_tendon">
  <site site="glmin2_r_glmin2_r-P1"/>
  <site site="glmin2_r_glmin2_r-P2"/>
</spatial>
<spatial name="glmin3_r_tendon">
  <site site="glmin3_r_glmin3_r-P1"/>
  <site site="glmin3_r_glmin3_r-P2"/>
</spatial>
<spatial name="grac_r_tendon">
  <site site="grac_r_grac_r-P1"/>
  <geom geom="GR_at_condyles_r_cylinder"
sidesite="GR_at_condyles_r_cylinder_grac_r_1_sidesite"/>
  <site site="grac_r_grac_r-P2"/>
  <site site="grac_r_grac_r-P3"/>
</spatial>
<spatial name="iliacus_r_tendon">
  <site site="iliacus_r_iliacus_r-P1"/>
  <site site="iliacus_r_iliacus_r-P2"/>
  <geom geom="IL_at_brim_r_cylinder"
sidesite="IL_at_brim_r_cylinder_iliacus_r_2_sidesite"/>
  <site site="iliacus_r_iliacus_r-P3"/>
  <site site="iliacus_r_iliacus_r-P4"/>
</spatial>
<spatial name="perbrev_r_tendon">
  <site site="perbrev_r_perbrev_r-P1"/>
  <site site="perbrev_r_perbrev_r-P2"/>
  <site site="perbrev_r_perbrev_r-P3"/>
  <site site="perbrev_r_perbrev_r-P4"/>
  <site site="perbrev_r_perbrev_r-P5"/>
</spatial>
<spatial name="perlong_r_tendon">
  <site site="perlong_r_perlong_r-P1"/>
  <site site="perlong_r_perlong_r-P2"/>
  <site site="perlong_r_perlong_r-P3"/>
  <site site="perlong_r_perlong_r-P4"/>
  <site site="perlong_r_perlong_r-P5"/>
  <site site="perlong_r_perlong_r-P6"/>
  <site site="perlong_r_perlong_r-P7"/>
</spatial>
<spatial name="piri_r_tendon">
  <site site="piri_r_piri_r-P1"/>
  <site site="piri_r_piri_r-P2"/>
  <site site="piri_r_piri_r-P3"/>
</spatial>
<spatial name="psoas_r_tendon">
  <site site="psoas_r_psoas_r-P1"/>
```

```xml
            <site site="psoas_r_psoas_r-P2"/>
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sidesite="PS_at_brim_r_cylinder_psoas_r_2_sidesite"/>
            <site site="psoas_r_psoas_r-P3"/>
            <site site="psoas_r_psoas_r-P4"/>
        </spatial>
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            <site site="recfem_r_recfem_r-P1"/>
            <site site="recfem_r_recfem_r-P2"/>
            <site site="recfem_r_recfem_r-P3"/>
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sidesite="KnExt_at_fem_r_cylinder_recfem_r_3_sidesite"/>
            <site site="recfem_r_recfem_r-P4"/>
            <site site="recfem_r_recfem_r-P5"/>
        </spatial>
        <spatial name="sart_r_tendon">
            <site site="sart_r_sart_r-P1"/>
            <site site="sart_r_sart_r-P2"/>
            <site site="sart_r_sart_r-P3"/>
            <site site="sart_r_sart_r-P4"/>
            <site site="sart_r_sart_r-P5"/>
        </spatial>
        <spatial name="semimem_r_tendon">
            <site site="semimem_r_semimem_r-P1"/>
            <geom geom="SM_at_condyles_r_cylinder"
sidesite="SM_at_condyles_r_cylinder_semimem_r_1_sidesite"/>
            <site site="semimem_r_semimem_r-P2"/>
        </spatial>
        <spatial name="semiten_r_tendon">
            <site site="semiten_r_semiten_r-P1"/>
            <geom geom="ST_at_condyles_r_cylinder"
sidesite="ST_at_condyles_r_cylinder_semiten_r_1_sidesite"/>
            <site site="semiten_r_semiten_r-P2"/>
            <site site="semiten_r_semiten_r-P3"/>
        </spatial>
        <spatial name="soleus_r_tendon">
            <site site="soleus_r_soleus_r-P1"/>
            <site site="soleus_r_soleus_r-P2"/>
        </spatial>
        <spatial name="tfl_r_tendon">
            <site site="tfl_r_tfl_r-P1"/>
            <site site="tfl_r_tfl_r-P2"/>
            <site site="tfl_r_tfl_r-P3"/>
            <site site="tfl_r_tfl_r-P4"/>
        </spatial>
        <spatial name="tibant_r_tendon">
            <site site="tibant_r_tibant_r-P1"/>
            <site site="tibant_r_tibant_r-P2"/>
            <site site="tibant_r_tibant_r-P3"/>
            <site site="tibant_r_tibant_r-P4"/>
```

```xml
    </spatial>
    <spatial name="tibpost_r_tendon">
      <site site="tibpost_r_tibpost_r-P1"/>
      <site site="tibpost_r_tibpost_r-P2"/>
      <site site="tibpost_r_tibpost_r-P3"/>
      <site site="tibpost_r_tibpost_r-P4"/>
    </spatial>
    <spatial name="vasint_r_tendon">
      <site site="vasint_r_vasint_r-P1"/>
      <site site="vasint_r_vasint_r-P2"/>
      <site site="vasint_r_vasint_r-P3"/>
      <geom geom="KnExt_at_fem_r_cylinder"
sidesite="KnExt_at_fem_r_cylinder_vasint_r_3_sidesite"/>
      <site site="vasint_r_vasint_r-P4"/>
      <site site="vasint_r_vasint_r-P5"/>
    </spatial>
    <spatial name="vaslat_r_tendon">
      <site site="vaslat_r_vaslat_r-P1"/>
      <site site="vaslat_r_vaslat_r-P2"/>
      <site site="vaslat_r_vaslat_r-P3"/>
      <geom geom="KnExt_at_fem_r_cylinder"
sidesite="KnExt_at_fem_r_cylinder_vaslat_r_3_sidesite"/>
      <site site="vaslat_r_vaslat_r-P4"/>
      <site site="vaslat_r_vaslat_r-P5"/>
    </spatial>
    <spatial name="vasmed_r_tendon">
      <site site="vasmed_r_vasmed_r-P1"/>
      <site site="vasmed_r_vasmed_r-P2"/>
      <site site="vasmed_r_vasmed_r-P3"/>
      <geom geom="KnExt_at_fem_r_cylinder"
sidesite="KnExt_at_fem_r_cylinder_vasmed_r_3_sidesite"/>
      <site site="vasmed_r_vasmed_r-P4"/>
      <geom geom="KnExt_at_fem_r_cylinder"
sidesite="KnExt_at_fem_r_cylinder_vasmed_r_4_sidesite"/>
      <site site="vasmed_r_vasmed_r-P5"/>
    </spatial>
    <spatial name="addbrev_l_tendon">
      <site site="addbrev_l_addbrev_l-P1"/>
      <geom geom="AB_at_femshaft_l_cylinder"
sidesite="AB_at_femshaft_l_cylinder_addbrev_l_1_sidesite"/>
      <site site="addbrev_l_addbrev_l-P2"/>
    </spatial>
    <spatial name="addlong_l_tendon">
      <site site="addlong_l_addlong_l-P1"/>
      <geom geom="AL_at_femshaft_l_cylinder"
sidesite="AL_at_femshaft_l_cylinder_addlong_l_1_sidesite"/>
      <site site="addlong_l_addlong_l-P2"/>
    </spatial>
    <spatial name="addmagDist_l_tendon">
      <site site="addmagDist_l_addmagDist_l-P1"/>
```

```xml
        <geom geom="AMdist_at_femshaft_l_cylinder"
sidesite="AMdist_at_femshaft_l_cylinder_addmagDist_l_1_sidesite"/>
          <site site="addmagDist_l_addmagDist_l-P2"/>
        </spatial>
        <spatial name="addmagIsch_l_tendon">
          <site site="addmagIsch_l_addmagIsch_l-P1"/>
          <geom geom="AMisch_at_condyles_l_cylinder"
sidesite="AMisch_at_condyles_l_cylinder_addmagIsch_l_1_sidesite"/>
          <site site="addmagIsch_l_addmagIsch_l-P2"/>
        </spatial>
        <spatial name="addmagMid_l_tendon">
          <site site="addmagMid_l_addmagMid_l-P1"/>
          <geom geom="AMmid_at_femshaft_l_cylinder"
sidesite="AMmid_at_femshaft_l_cylinder_addmagMid_l_1_sidesite"/>
          <site site="addmagMid_l_addmagMid_l-P2"/>
        </spatial>
        <spatial name="addmagProx_l_tendon">
          <site site="addmagProx_l_addmagProx_l-P1"/>
          <geom geom="AMprox_at_femshaft_l_cylinder"
sidesite="AMprox_at_femshaft_l_cylinder_addmagProx_l_1_sidesite"/>
          <site site="addmagProx_l_addmagProx_l-P2"/>
        </spatial>
        <spatial name="bflh_l_tendon">
          <site site="bflh_l_bflh_l-P1"/>
          <site site="bflh_l_bflh_l-P2"/>
          <site site="bflh_l_bflh_l-P3"/>
        </spatial>
        <spatial name="bfsh_l_tendon">
          <site site="bfsh_l_bfsh_l-P1"/>
          <site site="bfsh_l_bfsh_l-P2"/>
        </spatial>
        <spatial name="edl_l_tendon">
          <site site="edl_l_edl_l-P1"/>
          <site site="edl_l_edl_l-P2"/>
          <site site="edl_l_edl_l-P3"/>
          <site site="edl_l_edl_l-P4"/>
          <site site="edl_l_edl_l-P5"/>
          <site site="edl_l_edl_l-P6"/>
        </spatial>
        <spatial name="ehl_l_tendon">
          <site site="ehl_l_ehl_l-P1"/>
          <site site="ehl_l_ehl_l-P2"/>
          <site site="ehl_l_ehl_l-P3"/>
          <site site="ehl_l_ehl_l-P4"/>
          <site site="ehl_l_ehl_l-P5"/>
          <site site="ehl_l_ehl_l-P6"/>
          <site site="ehl_l_ehl_l-P7"/>
          <site site="ehl_l_ehl_l-P8"/>
        </spatial>
        <spatial name="fdl_l_tendon">
```

```xml
        <site site="fdl_l_fdl_l-P1"/>
        <site site="fdl_l_fdl_l-P2"/>
        <site site="fdl_l_fdl_l-P3"/>
        <site site="fdl_l_fdl_l-P4"/>
        <site site="fdl_l_fdl_l-P5"/>
        <site site="fdl_l_fdl_l-P6"/>
        <site site="fdl_l_fdl_l-P7"/>
        <site site="fdl_l_fdl_l-P8"/>
      </spatial>
      <spatial name="fhl_l_tendon">
        <site site="fhl_l_fhl_l-P1"/>
        <site site="fhl_l_fhl_l-P2"/>
        <site site="fhl_l_fhl_l-P3"/>
        <site site="fhl_l_fhl_l-P4"/>
        <site site="fhl_l_fhl_l-P5"/>
        <site site="fhl_l_fhl_l-P6"/>
        <site site="fhl_l_fhl_l-P7"/>
      </spatial>
      <spatial name="gaslat_l_tendon">
        <site site="gaslat_l_gaslat_l-P1"/>
        <geom geom="Gastroc_at_condyles_l_cylinder"
sidesite="Gastroc_at_condyles_l_cylinder_gaslat_l_1_sidesite"/>
        <site site="gaslat_l_gaslat_l-P2"/>
      </spatial>
      <spatial name="gasmed_l_tendon">
        <site site="gasmed_l_gasmed_l-P1"/>
        <geom geom="Gastroc_at_condyles_l_cylinder"
sidesite="Gastroc_at_condyles_l_cylinder_gasmed_l_1_sidesite"/>
        <site site="gasmed_l_gasmed_l-P2"/>
      </spatial>
      <spatial name="glmax1_l_tendon">
        <site site="glmax1_l_glmax1_l-P1"/>
        <site site="glmax1_l_glmax1_l-P2"/>
        <geom geom="Gmax1_at_pelvis_l_cylinder"
sidesite="Gmax1_at_pelvis_l_cylinder_glmax1_l_2_sidesite"/>
        <site site="glmax1_l_glmax1_l-P3"/>
        <site site="glmax1_l_glmax1_l-P4"/>
      </spatial>
      <spatial name="glmax2_l_tendon">
        <site site="glmax2_l_glmax2_l-P1"/>
        <site site="glmax2_l_glmax2_l-P2"/>
        <geom geom="Gmax2_at_pelvis_l_cylinder"
sidesite="Gmax2_at_pelvis_l_cylinder_glmax2_l_2_sidesite"/>
        <site site="glmax2_l_glmax2_l-P3"/>
        <site site="glmax2_l_glmax2_l-P4"/>
      </spatial>
      <spatial name="glmax3_l_tendon">
        <site site="glmax3_l_glmax3_l-P1"/>
        <geom geom="Gmax3_at_pelvis_l_cylinder"
sidesite="Gmax3_at_pelvis_l_cylinder_glmax3_l_1_sidesite"/>
```

```xml
        <site site="glmax3_l_glmax3_l-P2"/>
        <site site="glmax3_l_glmax3_l-P3"/>
        <site site="glmax3_l_glmax3_l-P4"/>
      </spatial>
      <spatial name="glmed1_l_tendon">
        <site site="glmed1_l_glmed1_l-P1"/>
        <site site="glmed1_l_glmed1_l-P2"/>
      </spatial>
      <spatial name="glmed2_l_tendon">
        <site site="glmed2_l_glmed2_l-P1"/>
        <site site="glmed2_l_glmed2_l-P2"/>
      </spatial>
      <spatial name="glmed3_l_tendon">
        <site site="glmed3_l_glmed3_l-P1"/>
        <site site="glmed3_l_glmed3_l-P2"/>
      </spatial>
      <spatial name="glmin1_l_tendon">
        <site site="glmin1_l_glmin1_l-P1"/>
        <site site="glmin1_l_glmin1_l-P2"/>
      </spatial>
      <spatial name="glmin2_l_tendon">
        <site site="glmin2_l_glmin2_l-P1"/>
        <site site="glmin2_l_glmin2_l-P2"/>
      </spatial>
      <spatial name="glmin3_l_tendon">
        <site site="glmin3_l_glmin3_l-P1"/>
        <site site="glmin3_l_glmin3_l-P2"/>
      </spatial>
      <spatial name="grac_l_tendon">
        <site site="grac_l_grac_l-P1"/>
        <geom geom="GR_at_condyles_l_cylinder"
  sidesite="GR_at_condyles_l_cylinder_grac_l_1_sidesite"/>
        <site site="grac_l_grac_l-P2"/>
        <site site="grac_l_grac_l-P3"/>
      </spatial>
      <spatial name="iliacus_l_tendon">
        <site site="iliacus_l_iliacus_l-P1"/>
        <site site="iliacus_l_iliacus_l-P2"/>
        <geom geom="IL_at_brim_l_cylinder"
  sidesite="IL_at_brim_l_cylinder_iliacus_l_2_sidesite"/>
        <site site="iliacus_l_iliacus_l-P3"/>
        <site site="iliacus_l_iliacus_l-P4"/>
      </spatial>
      <spatial name="perbrev_l_tendon">
        <site site="perbrev_l_perbrev_l-P1"/>
        <site site="perbrev_l_perbrev_l-P2"/>
        <site site="perbrev_l_perbrev_l-P3"/>
        <site site="perbrev_l_perbrev_l-P4"/>
        <site site="perbrev_l_perbrev_l-P5"/>
      </spatial>
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```xml
<spatial name="perlong_l_tendon">
  <site site="perlong_l_perlong_l-P1"/>
  <site site="perlong_l_perlong_l-P2"/>
  <site site="perlong_l_perlong_l-P3"/>
  <site site="perlong_l_perlong_l-P4"/>
  <site site="perlong_l_perlong_l-P5"/>
  <site site="perlong_l_perlong_l-P6"/>
  <site site="perlong_l_perlong_l-P7"/>
</spatial>
<spatial name="piri_l_tendon">
  <site site="piri_l_piri_l-P1"/>
  <site site="piri_l_piri_l-P2"/>
  <site site="piri_l_piri_l-P3"/>
</spatial>
<spatial name="psoas_l_tendon">
  <site site="psoas_l_psoas_l-P1"/>
  <site site="psoas_l_psoas_l-P2"/>
  <geom geom="PS_at_brim_l_cylinder"
sidesite="PS_at_brim_l_cylinder_psoas_l_2_sidesite"/>
  <site site="psoas_l_psoas_l-P3"/>
  <site site="psoas_l_psoas_l-P4"/>
</spatial>
<spatial name="recfem_l_tendon">
  <site site="recfem_l_recfem_l-P1"/>
  <site site="recfem_l_recfem_l-P2"/>
  <site site="recfem_l_recfem_l-P3"/>
  <geom geom="KnExt_at_fem_l_cylinder"
sidesite="KnExt_at_fem_l_cylinder_recfem_l_3_sidesite"/>
  <site site="recfem_l_recfem_l-P4"/>
  <site site="recfem_l_recfem_l-P5"/>
</spatial>
<spatial name="sart_l_tendon">
  <site site="sart_l_sart_l-P1"/>
  <site site="sart_l_sart_l-P2"/>
  <site site="sart_l_sart_l-P3"/>
  <site site="sart_l_sart_l-P4"/>
  <site site="sart_l_sart_l-P5"/>
</spatial>
<spatial name="semimem_l_tendon">
  <site site="semimem_l_semimem_l-P1"/>
  <geom geom="SM_at_condyles_l_cylinder"
sidesite="SM_at_condyles_l_cylinder_semimem_l_1_sidesite"/>
  <site site="semimem_l_semimem_l-P2"/>
</spatial>
<spatial name="semiten_l_tendon">
  <site site="semiten_l_semiten_l-P1"/>
  <geom geom="ST_at_condyles_l_cylinder"
sidesite="ST_at_condyles_l_cylinder_semiten_l_1_sidesite"/>
  <site site="semiten_l_semiten_l-P2"/>
  <site site="semiten_l_semiten_l-P3"/>
```

```xml
        </spatial>
        <spatial name="soleus_l_tendon">
          <site site="soleus_l_soleus_l-P1"/>
          <site site="soleus_l_soleus_l-P2"/>
        </spatial>
        <spatial name="tfl_l_tendon">
          <site site="tfl_l_tfl_l-P1"/>
          <site site="tfl_l_tfl_l-P2"/>
          <site site="tfl_l_tfl_l-P3"/>
          <site site="tfl_l_tfl_l-P4"/>
        </spatial>
        <spatial name="tibant_l_tendon">
          <site site="tibant_l_tibant_l-P1"/>
          <site site="tibant_l_tibant_l-P2"/>
          <site site="tibant_l_tibant_l-P3"/>
          <site site="tibant_l_tibant_l-P4"/>
        </spatial>
        <spatial name="tibpost_l_tendon">
          <site site="tibpost_l_tibpost_l-P1"/>
          <site site="tibpost_l_tibpost_l-P2"/>
          <site site="tibpost_l_tibpost_l-P3"/>
          <site site="tibpost_l_tibpost_l-P4"/>
        </spatial>
        <spatial name="vasint_l_tendon">
          <site site="vasint_l_vasint_l-P1"/>
          <site site="vasint_l_vasint_l-P2"/>
          <site site="vasint_l_vasint_l-P3"/>
          <geom geom="KnExt_at_fem_l_cylinder"
sidesite="KnExt_at_fem_l_cylinder_vasint_l_3_sidesite"/>
          <site site="vasint_l_vasint_l-P4"/>
          <site site="vasint_l_vasint_l-P5"/>
        </spatial>
        <spatial name="vaslat_l_tendon">
          <site site="vaslat_l_vaslat_l-P1"/>
          <site site="vaslat_l_vaslat_l-P2"/>
          <site site="vaslat_l_vaslat_l-P3"/>
          <geom geom="KnExt_at_fem_l_cylinder"
sidesite="KnExt_at_fem_l_cylinder_vaslat_l_3_sidesite"/>
          <site site="vaslat_l_vaslat_l-P4"/>
          <site site="vaslat_l_vaslat_l-P5"/>
        </spatial>
        <spatial name="vasmed_l_tendon">
          <site site="vasmed_l_vasmed_l-P1"/>
          <site site="vasmed_l_vasmed_l-P2"/>
          <site site="vasmed_l_vasmed_l-P3"/>
          <geom geom="KnExt_at_fem_l_cylinder"
sidesite="KnExt_at_fem_l_cylinder_vasmed_l_3_sidesite"/>
          <site site="vasmed_l_vasmed_l-P4"/>
          <geom geom="KnExt_at_fem_l_cylinder"
sidesite="KnExt_at_fem_l_cylinder_vasmed_l_4_sidesite"/>
```

```xml
          <site site="vasmed_l_vasmed_l-P5"/>
        </spatial>
      </tendon>
      <actuator>
        <general name="lumbar_ext" class="motor" joint="lumbar_extension" gainprm="1
0 1 1 0 0 0 0 0 0"/>
        <general name="lumbar_bend" class="motor" joint="lumbar_bending" gainprm="1
0 1 1 0 0 0 0 0 0"/>
        <general name="lumbar_rot" class="motor" joint="lumbar_rotation" gainprm="1 0
1 1 0 0 0 0 0 0"/>
        <general name="shoulder_flex_r" class="motor" joint="arm_flex_r" gainprm="1 0 1
1 0 0 0 0 0 0"/>
        <general name="shoulder_add_r" class="motor" joint="arm_add_r" gainprm="1 0
1 1 0 0 0 0 0 0"/>
        <general name="shoulder_rot_r" class="motor" joint="arm_rot_r" gainprm="1 0 1
1 0 0 0 0 0 0"/>
        <general name="elbow_flex_r" class="motor" joint="elbow_flex_r" gainprm="1 0 1
1 0 0 0 0 0 0"/>
        <general name="pro_sup_r" class="motor" joint="pro_sup_r" gainprm="1 0 1 1 0 0
0 0 0 0"/>
        <general name="wrist_flex_r" class="motor" joint="wrist_flex_r" gainprm="1 0 1 1
0 0 0 0 0 0"/>
        <general name="wrist_dev_r" class="motor" joint="wrist_dev_r" gainprm="1 0 1 1
0 0 0 0 0 0"/>
        <general name="shoulder_flex_l" class="motor" joint="arm_flex_l" gainprm="1 0 1
1 0 0 0 0 0 0"/>
        <general name="shoulder_add_l" class="motor" joint="arm_add_l" gainprm="1 0 1
1 0 0 0 0 0 0"/>
        <general name="shoulder_rot_l" class="motor" joint="arm_rot_l" gainprm="1 0 1 1
0 0 0 0 0 0"/>
        <general name="elbow_flex_l" class="motor" joint="elbow_flex_l" gainprm="1 0 1
1 0 0 0 0 0 0"/>
        <general name="pro_sup_l" class="motor" joint="pro_sup_l" gainprm="1 0 1 1 0 0
0 0 0 0"/>
        <general name="wrist_flex_l" class="motor" joint="wrist_flex_l" gainprm="1 0 1 1 0
0 0 0 0 0"/>
        <general name="wrist_dev_l" class="motor" joint="wrist_dev_l" gainprm="1 0 1 1
0 0 0 0 0 0"/>
        <general name="addbrev_r" class="muscle" tendon="addbrev_r_tendon"
lengthrange="0.0748213 0.186183" gainprm="0.342837 1.51768 602.632 1 0 2 10
0.754939 1.4 0" biasprm="0.342837 1.51768 602.632 1 0 2 10 0.754939 1.4 0"/>
        <general name="addlong_r" class="muscle" tendon="addlong_r_tendon"
lengthrange="0.170922 0.301501" gainprm="0.310148 1.48929 876.22 1 0 2 10
0.805547 1.4 0" biasprm="0.310148 1.48929 876.22 1 0 2 10 0.805547 1.4 0"/>
        <general name="addmagDist_r" class="muscle" tendon="addmagDist_r_tendon"
lengthrange="0.202039 0.322256" gainprm="0.75882 1.0598 547.461 1 0 2 10
3.17593 1.4 0" biasprm="0.75882 1.0598 547.461 1 0 2 10 3.17593 1.4 0"/>
        <general name="addmagIsch_r" class="muscle" tendon="addmagIsch_r_tendon"
lengthrange="0.319892 0.45801" gainprm="0.702124 1.15264 546.509 1 0 2 10
1.76582 1.4 0" biasprm="0.702124 1.15264 546.509 1 0 2 10 1.76582 1.4 0"/>
```

```
<general name="addmagMid_r" class="muscle" tendon="addmagMid_r_tendon"
lengthrange="0.112433 0.222783" gainprm="0.45464 1.43959 567.74 1 0 2 10
0.710131 1.4 0" biasprm="0.45464 1.43959 567.74 1 0 2 10 0.710131 1.4 0"/>
   <general name="addmagProx_r" class="muscle" tendon="addmagProx_r_tendon"
lengthrange="0.0575134 0.156741" gainprm="0.168219 1.1592 555.641 1 0 2 10
1.23451 1.4 0" biasprm="0.168219 1.1592 555.641 1 0 2 10 1.23451 1.4 0"/>
   <general name="bflh_r" class="muscle" tendon="bflh_r_tendon"
lengthrange="0.311066 0.518255" gainprm="0.0829535 1.45667 1199.48 1 0 2 10
2.0695 1.4 0" biasprm="0.0829535 1.45667 1199.48 1 0 2 10 2.0695 1.4 0"/>
   <general name="bfsh_r" class="muscle" tendon="bfsh_r_tendon"
lengthrange="0.150604 0.237912" gainprm="0.614405 1.31092 521.278 1 0 2 10
0.783598 1.4 0" biasprm="0.614405 1.31092 521.278 1 0 2 10 0.783598 1.4 0"/>
   <general name="edl_r" class="muscle" tendon="edl_r_tendon"
lengthrange="0.418089 0.460181" gainprm="0.527256 1.1111 568.779 1 0 2 10
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0.822429 1.4 0" biasprm="0.8549 1.66416 1198.27 1 0 2 10 0.822429 1.4 0"/>
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0.959945 1.4 0" biasprm="0.743481 1.76731 1248.41 1 0 2 10 0.959945 1.4 0"/>
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2.97481 1.4 0" biasprm="0.648407 1.25841 828.469 1 0 2 10 2.97481 1.4 0"/>
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1.00602 1.4 0" biasprm="0.173148 1.57426 946.79 1 0 2 10 1.00602 1.4 0"/>
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0.902986 1.4 0" biasprm="0.14917 1.60245 692.63 1 0 2 10 0.902986 1.4 0"/>
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1.02784 1.4 0" biasprm="0.180744 1.69346 755.042 1 0 2 10 1.02784 1.4 0"/>
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1.22287 1.4 0" biasprm="0.155617 1.41269 337.271 1 0 2 10 1.22287 1.4 0"/>
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1.59027 1.4 0" biasprm="0.157343 1.31427 372.428 1 0 2 10 1.59027 1.4 0"/>
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    <general name="grac_r" class="muscle" tendon="grac_r_tendon"
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3.38341 1.4 0" biasprm="0.751684 1.13634 941.464 1 0 2 10 3.38341 1.4 0"/>
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0.577274 1.4 0" biasprm="0.478034 1.34014 1370.6 1 0 2 10 0.577274 1.4 0"/>
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1.40758 1.4 0" biasprm="0.469068 1.38591 544.254 1 0 2 10 1.40758 1.4 0"/>
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1.33707 1.4 0" biasprm="0.504312 1.39524 1107.91 1 0 2 10 1.33707 1.4 0"/>
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2.3084 1.4 0" biasprm="0.625227 1.22103 1357.85 1 0 2 10 2.3084 1.4 0"/>
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2.43021 1.4 0" biasprm="0.880601 1.06163 1554.14 1 0 2 10 2.43021 1.4 0"/>
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0.48763 1.4 0" biasprm="0.590132 1.52727 5890.97 1 0 2 10 0.48763 1.4 0"/>
    <general name="vasmed_r" class="muscle" tendon="vasmed_r_tendon"
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0.771811 1.4 0" biasprm="0.699931 1.52806 2489.71 1 0 2 10 0.771811 1.4 0"/>
    <general name="addbrev_l" class="muscle" tendon="addbrev_l_tendon"
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0.812677 1.4 0" biasprm="0.328667 1.62353 598.604 1 0 2 10 0.812677 1.4 0"/>
    <general name="addlong_l" class="muscle" tendon="addlong_l_tendon"
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0.836822 1.4 0" biasprm="0.310034 1.46937 874.751 1 0 2 10 0.836822 1.4 0"/>
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0.720303 1.4 0" biasprm="0.626085 1.53768 578.018 1 0 2 10 0.720303 1.4 0"/>
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0.832918 1.4 0" biasprm="0.603769 1.67147 567.529 1 0 2 10 0.832918 1.4 0"/>
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0.342764 1.4 0" biasprm="0.462032 1.33347 576.674 1 0 2 10 0.342764 1.4 0"/>
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1.50695 1.4 0" biasprm="0.124747 1.32737 527.33 1 0 2 10 1.50695 1.4 0"/>
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    <general name="bfsh_l" class="muscle" tendon="bfsh_l_tendon"
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0.876777 1.4 0" biasprm="0.614126 1.44256 519.24 1 0 2 10 0.876777 1.4 0"/>
    <general name="edl_l" class="muscle" tendon="edl_l_tendon"
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1.65462 1.4 0" biasprm="0.527815 1.26078 549.67 1 0 2 10 1.65462 1.4 0"/>
    <general name="ehl_l" class="muscle" tendon="ehl_l_tendon"
lengthrange="0.383686 0.42895" gainprm="0.593178 1.4215 266.529 1 0 2 10
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    <general name="fdl_l" class="muscle" tendon="fdl_l_tendon"
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1.97958 1.4 0" biasprm="0.584735 1.31218 665.533 1 0 2 10 1.97958 1.4 0"/>
    <general name="gaslat_l" class="muscle" tendon="gaslat_l_tendon"
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    <general name="gasmed_l" class="muscle" tendon="gasmed_l_tendon"
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1.4 0" biasprm="1 1.00316 1177.65 1 0 2 10 1.72592 1.4 0"/>
    <general name="glmax2_l" class="muscle" tendon="glmax2_l_tendon"
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1.00546 1.4 0" biasprm="0.756036 1.71596 1240.53 1 0 2 10 1.00546 1.4 0"/>
    <general name="glmax3_l" class="muscle" tendon="glmax3_l_tendon"
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3.9434 1.4 0" biasprm="0.654623 1.21274 831.093 1 0 2 10 3.9434 1.4 0"/>
    <general name="glmed1_l" class="muscle" tendon="glmed1_l_tendon"
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0.929449 1.4 0" biasprm="0.127779 1.63323 977.269 1 0 2 10 0.929449 1.4 0"/>
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3.40039 1.4 0" biasprm="0.0105864 1.2193 422.934 1 0 2 10 3.40039 1.4 0"/>
    <general name="grac_l" class="muscle" tendon="grac_l_tendon"
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    <general name="iliacus_l" class="muscle" tendon="iliacus_l_tendon"
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    <general name="perbrev_l" class="muscle" tendon="perbrev_l_tendon"
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    <general name="psoas_l" class="muscle" tendon="psoas_l_tendon"
lengthrange="0.157713 0.242661" gainprm="0.497815 1.32289 1324.38 1 0 2 10
1.12521 1.4 0" biasprm="0.497815 1.32289 1324.38 1 0 2 10 1.12521 1.4 0"/>
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0.973925 1.4 0" biasprm="0.593727 1.46602 241.27 1 0 2 10 0.973925 1.4 0"/>
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    <general name="soleus_l" class="muscle" tendon="soleus_l_tendon"
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    <general name="tfl_l" class="muscle" tendon="tfl_l_tendon"
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1.85065 1.4 0" biasprm="0.0184669 1.08568 309.946 1 0 2 10 1.85065 1.4 0"/>
    <general name="tibant_l" class="muscle" tendon="tibant_l_tendon"
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1.88664 1.4 0" biasprm="0.514457 1.18148 1147.23 1 0 2 10 1.88664 1.4 0"/>
    <general name="tibpost_l" class="muscle" tendon="tibpost_l_tendon"
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    <general name="vaslat_l" class="muscle" tendon="vaslat_l_tendon"
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    <general name="vasmed_l" class="muscle" tendon="vasmed_l_tendon"
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-7.693e-11 0 -1.473e-08 -1.089e-08 0 0 0 0.05242 -0.01083 -0.00275 0.01051 0 0 0
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