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The 60 StepsIminute Cadence, And 25.3 Seconds At 162.1 Hz For The 95 StepsIminute Cadence. Research Design A Randomized Block Design Was Used In This Study. The Four Test Con- Ditions Included Forward Stair Step Ping At 35, 60, And 95 Steps/minute, And Retrograde Stair Stepping At 60 StepsIminute. To Determine Reliabil- Mar 2th, 2024

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Perry (1995) Recommend A Number Of 25 Repetitions As Normal [18]. Range Of Motion Of The Lower Extremity Was Measured By The Neutral-zero-method. The Assessment Of The Tibia Torsion Was Estimated By The Measurement Of The Transmalleollar Axis [19]. Stair Climbing And Gait Analysis Three-dimensional Lower Body Kinematics And Kinetics Were Apr 17th, 2024

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Power Sources, Charger Circuit, Motors (DC Motor, Servo Motor, Stepper Motor), And Wireless And Wire Modules. The Brain Of The Robot Is PIC16F877A. The Following Sections Describe In Details Each Of These Components. Figure (4) Block Diagram Of The Stair-Climbing Robot . Power Sources . Primary Source Of Power For The Robot Are Lithium May 3th, 2024

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Mm) Walk Line Within Any Flight Of Stairs Shall Not Exceed The Smallest By More Than 0.375 Inch (9.5 Mm) Measured At A Right Angle To The Tread's Leading Edge. Exceptions: 1. Nonuniform Riser Dimensions Of Aisle Stairs Complying With Section 1025.11.2. 2. Consistently Shaped Winders, Mar 15th, 2024

Deck, Porch, Landing, Stair, Ramp, And Guard Construction

C. Guards Shall Not Have Openings From The Walking Surface To The Required Guard Height Which Allow Passage Of A Sphere 4 Inches In Diameter. Exceptions: I. The Triangular Openings At The Open Side Of A Stair, Formed By The Riser, Tread And Bottom Rail Of A Guard, Shall Not Allow Pass Feb 4th, 2024

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