Hi, I am trying to simulate human lower limb cad model in simscape multibody using inverse dyanamics priniciple of robotics. I have the 3d model of human lower limb which is imported into simscape multibody. I need support to build human walking trajectory including joint angle , velocity and acceleration.This data would be used to calculate the torque required using newtons recursive algorithm. The torque calculated would be fed into simscape model.I shall get the same trajectory as output using control system.I am facing difficulty in trajectory and control system in matlab.