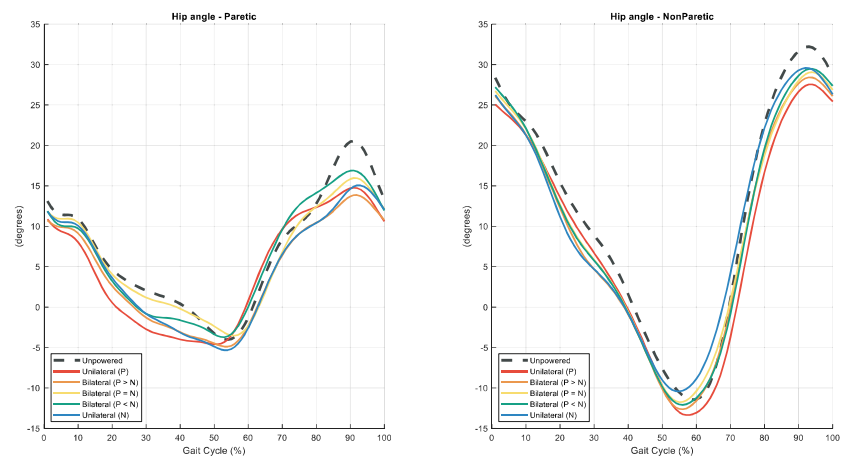


Supplemental Document: Individual joint kinematics across assistance conditions

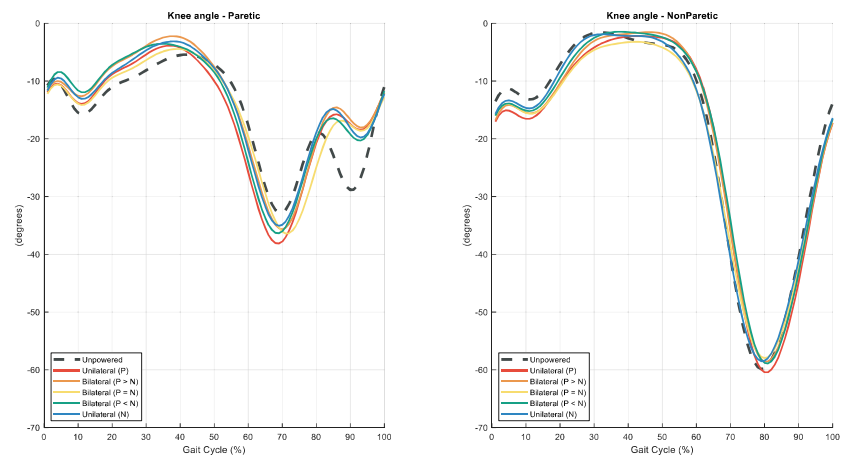
Experimental setup: In addition to the original data recordings, standard motion capture data was collected to calculate the joint kinematics (hip, knee, and ankle) across different exoskeleton assistance conditions. Different colors represent different assistance strategies, and a black dashed line represents the baseline condition of walking with the exoskeleton powered off (zero torque). The Left and right graph represent the subject's paretic and non-paretic side, respectively.

Supp. Fig. 1. Hip, knee, and ankle joint position across 5 different exoskeleton assistance strategies for paretic and non-paretic side

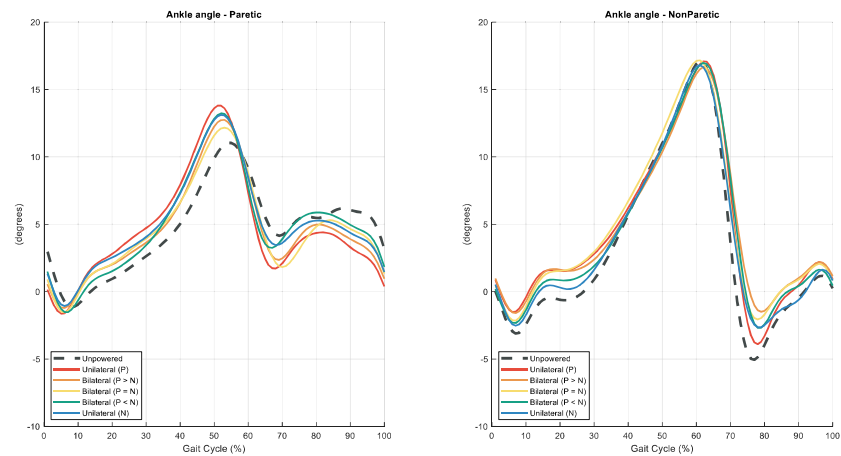
Hip joint position for ST01



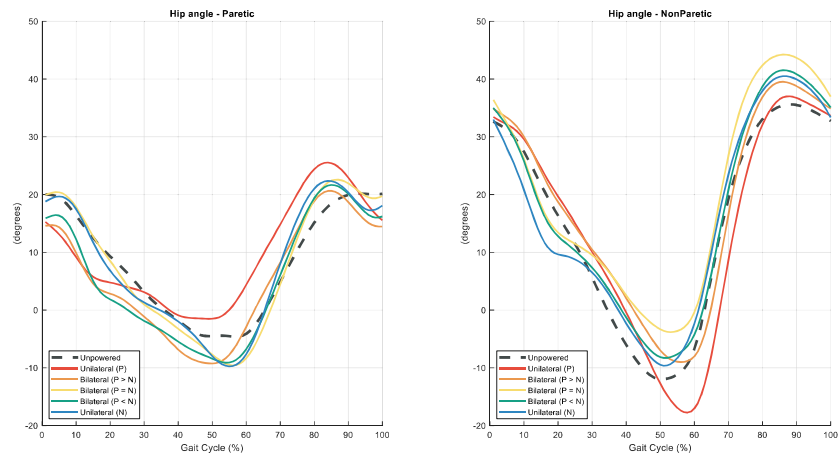
Knee joint position for ST01



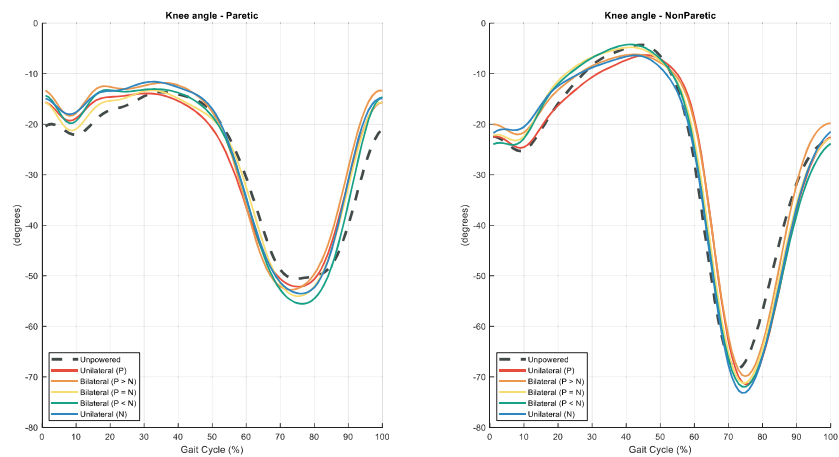
Ankle joint position for ST01



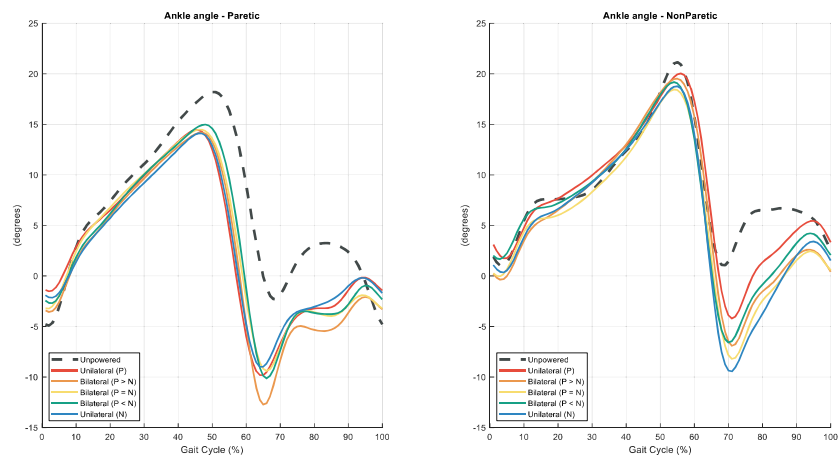
Hip joint position for ST02



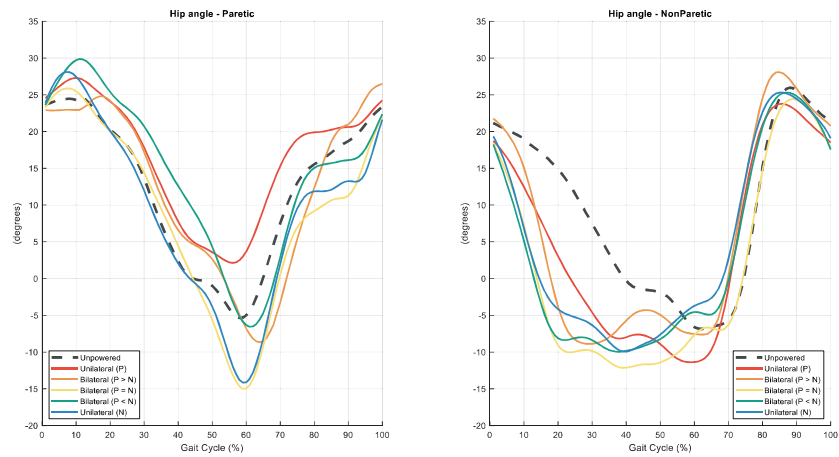
Knee joint position for ST02



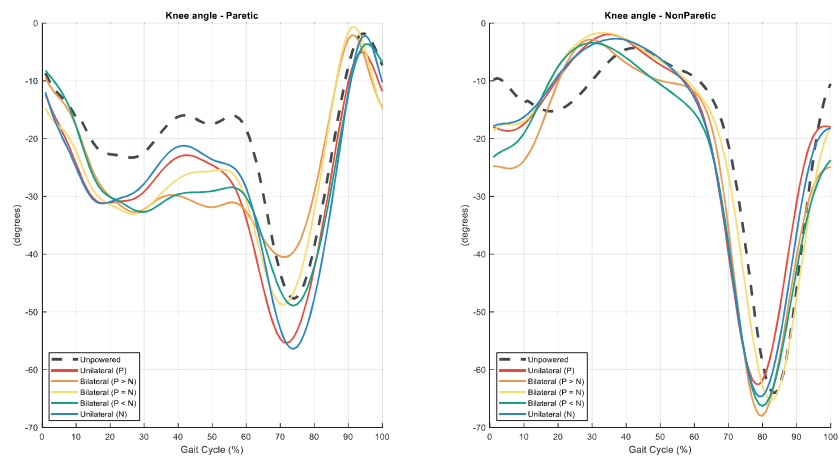
Ankle joint position for ST02



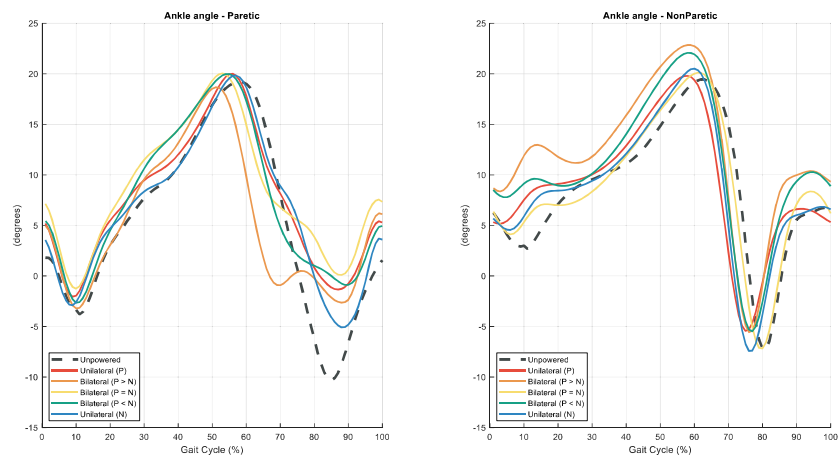
Hip joint position for ST03



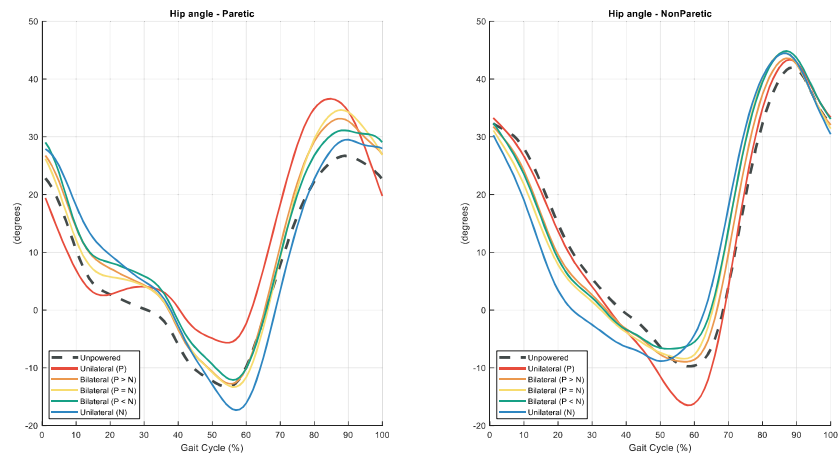
Knee joint position for ST03



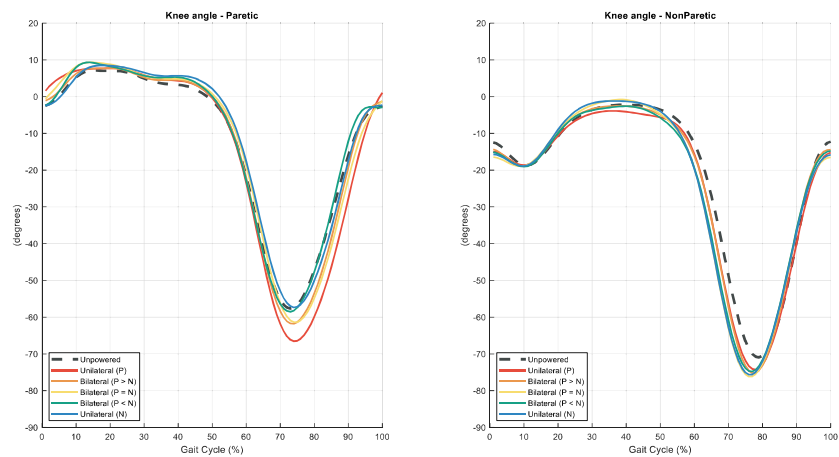
Ankle joint position for ST03



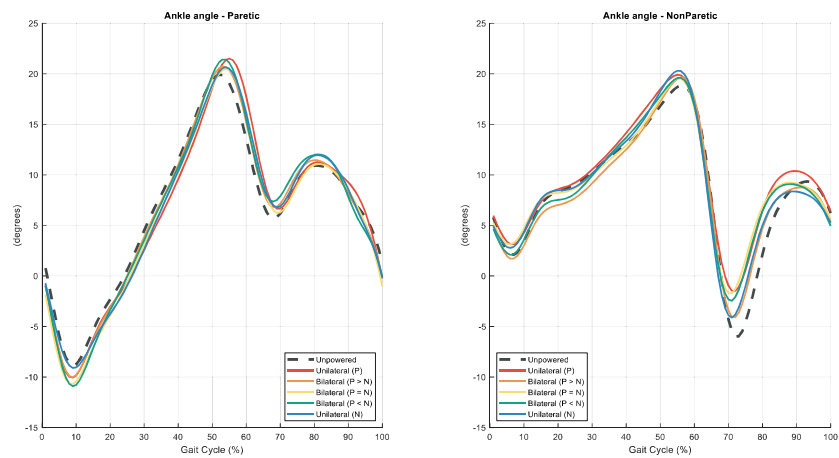
Hip joint position for ST04



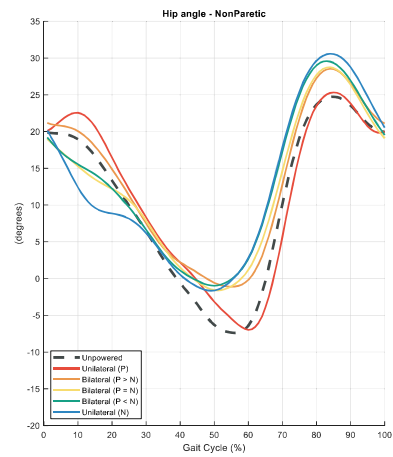
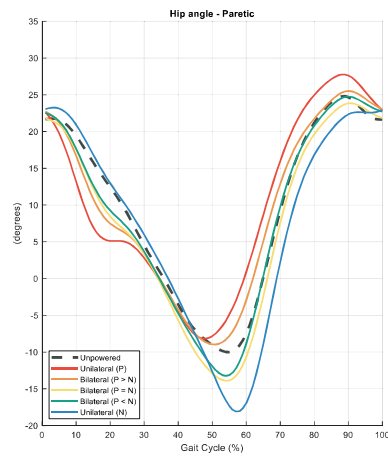
Knee joint position for ST04



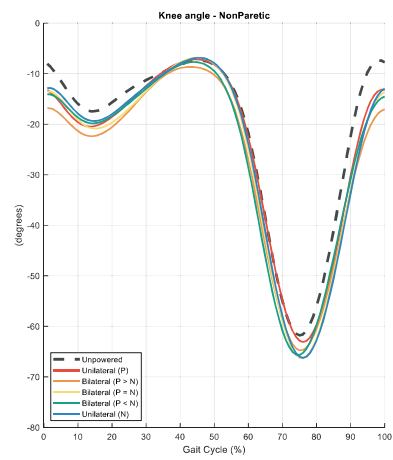
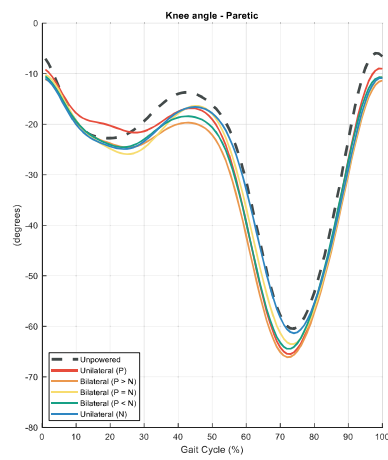
Ankle joint position for ST04



Hip joint position for ST05



Knee joint position for ST05



Ankle joint position for ST05

