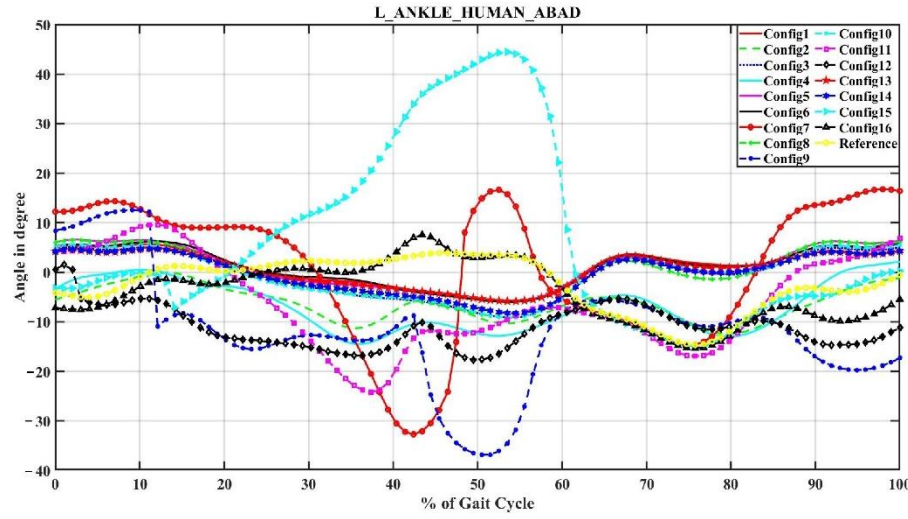
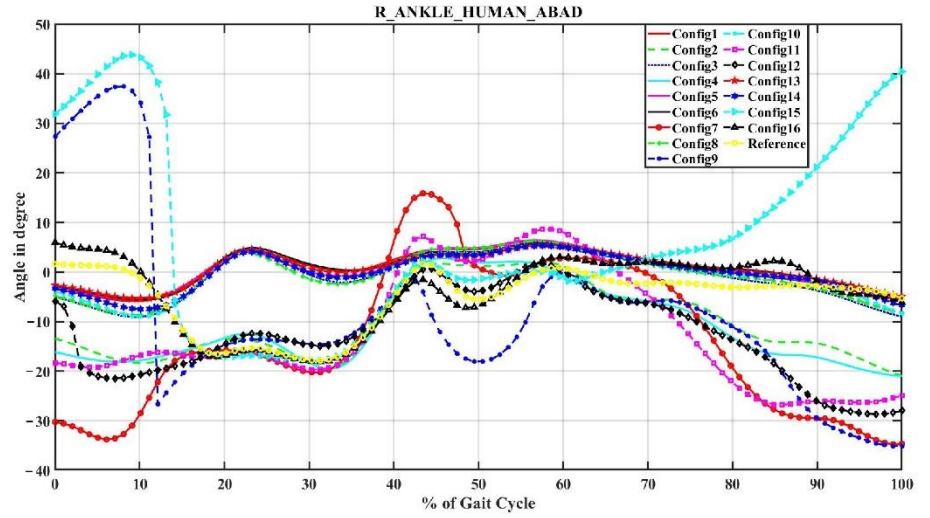


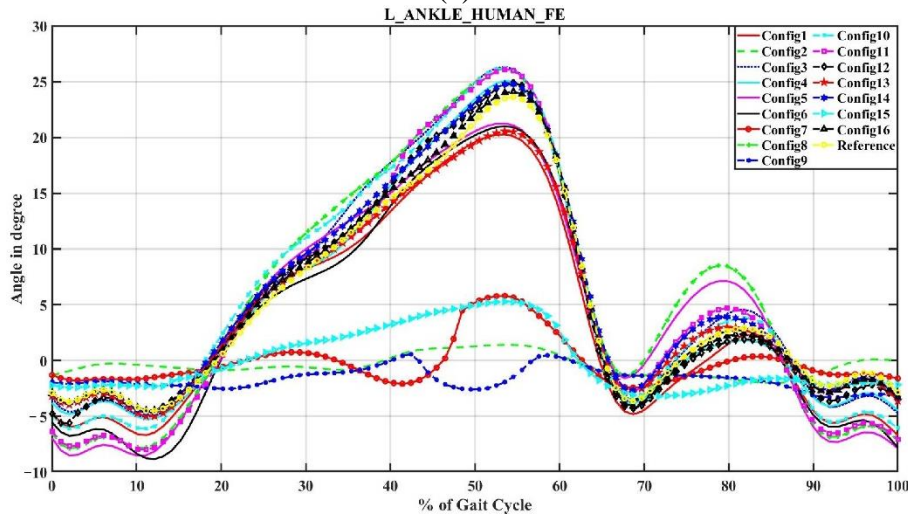
Range of motion of the hip, knee and ankle joints of human and exoskeleton simulated for one gait cycle across all 16 configurations



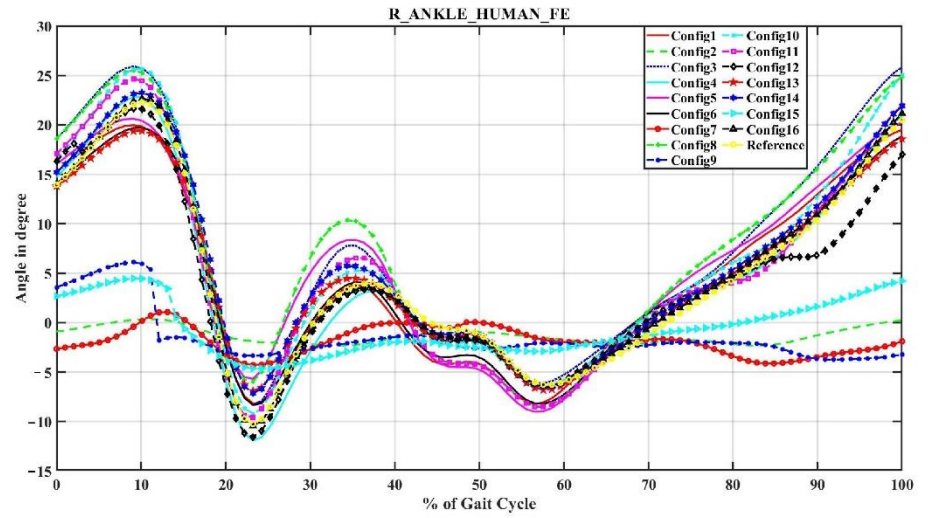
(c)



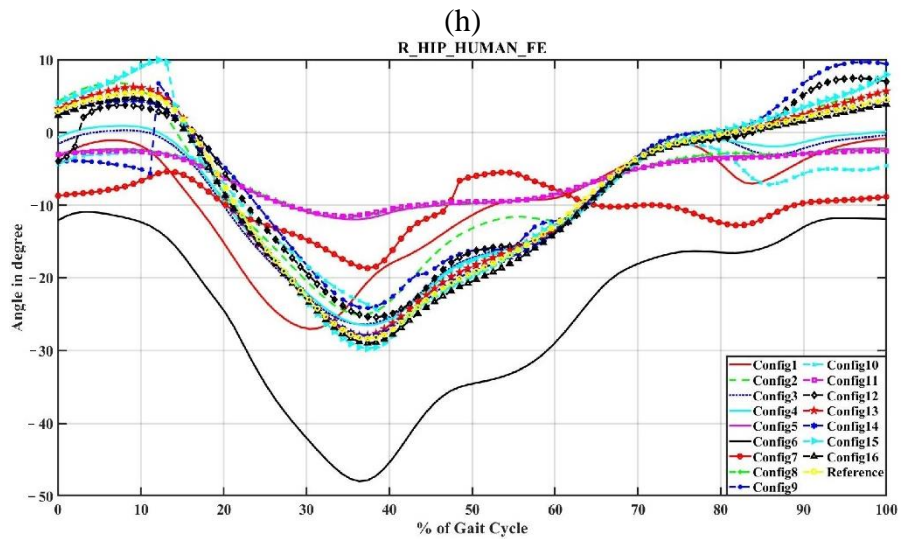
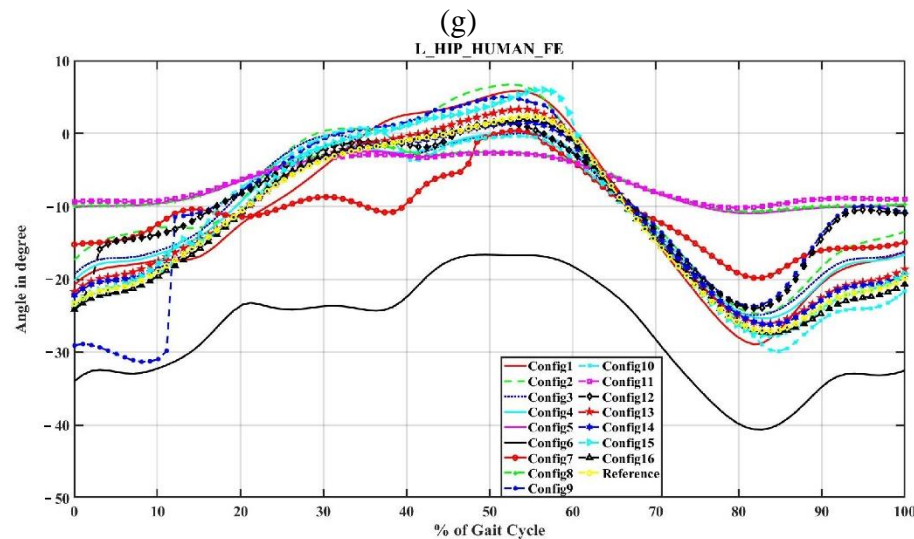
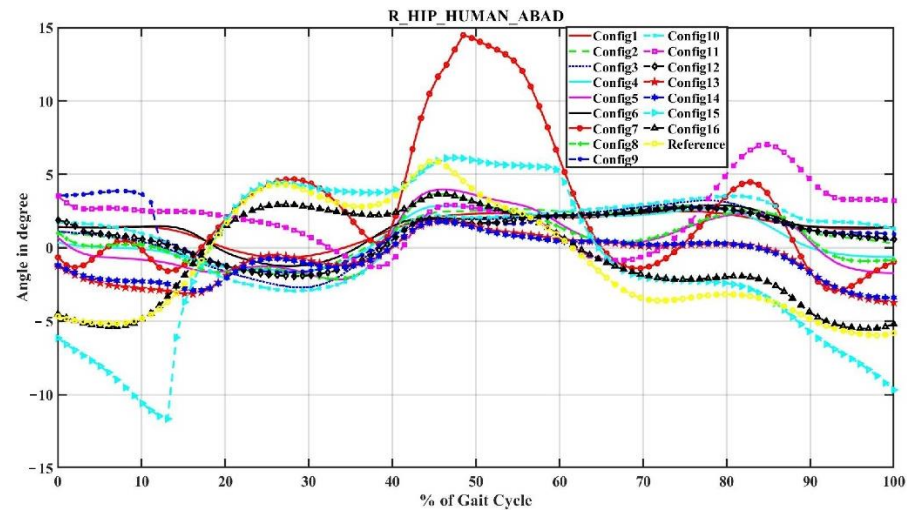
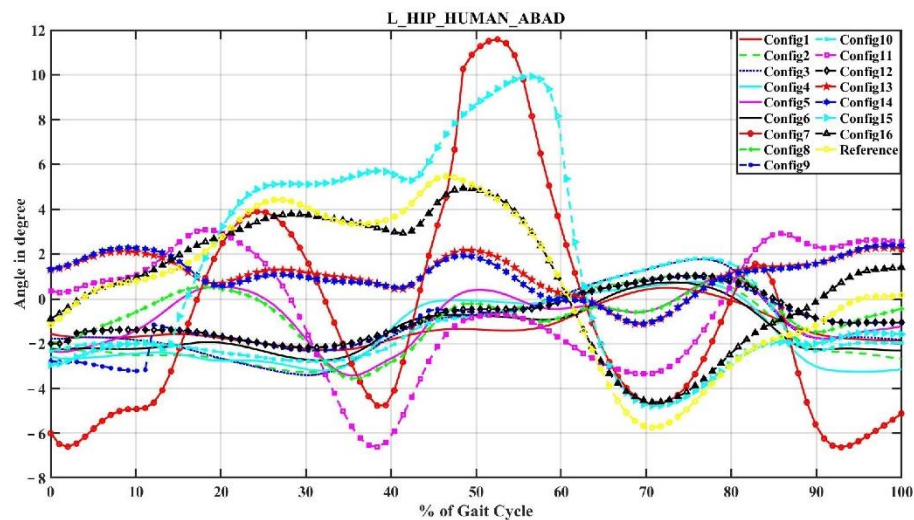
(d)



(e)

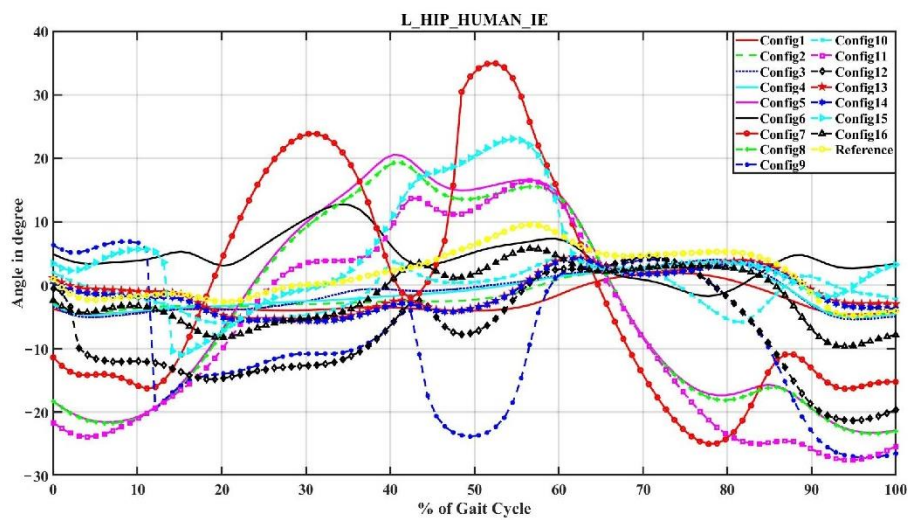


(f)

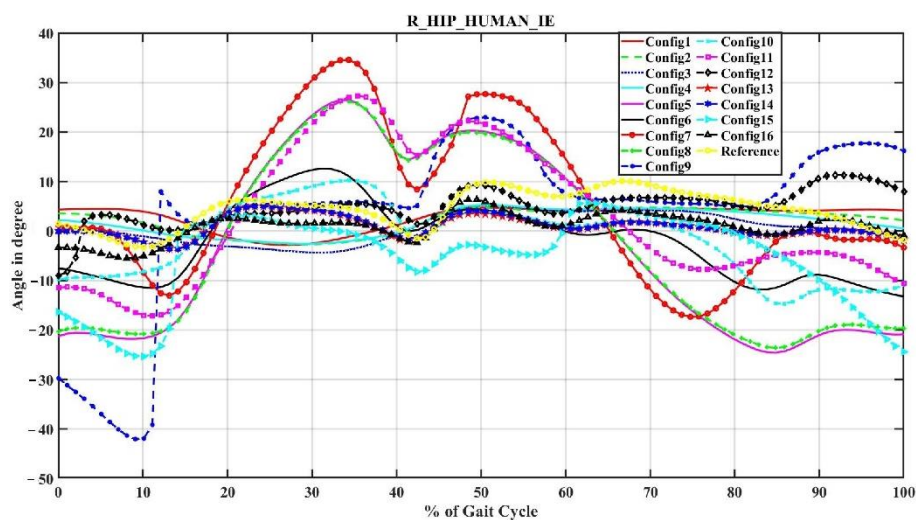


(i)

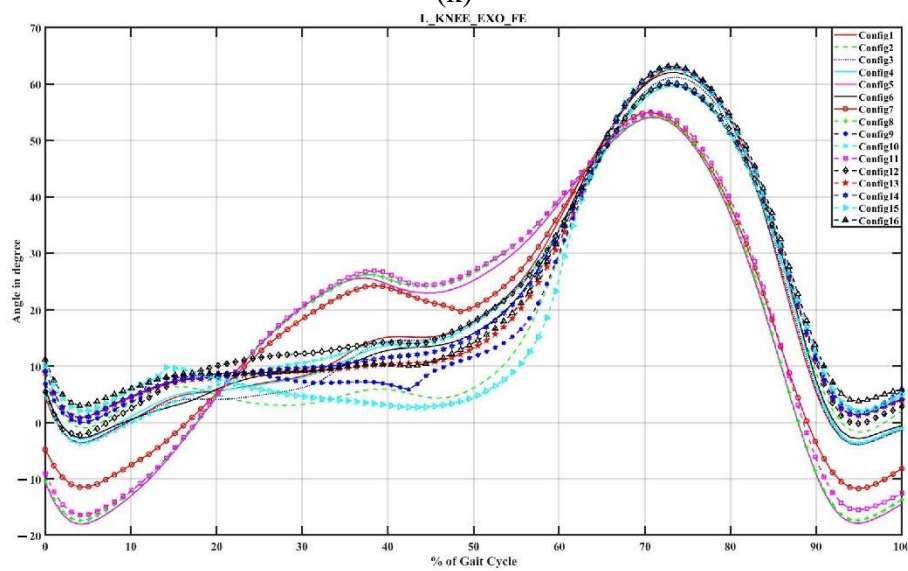
(j)



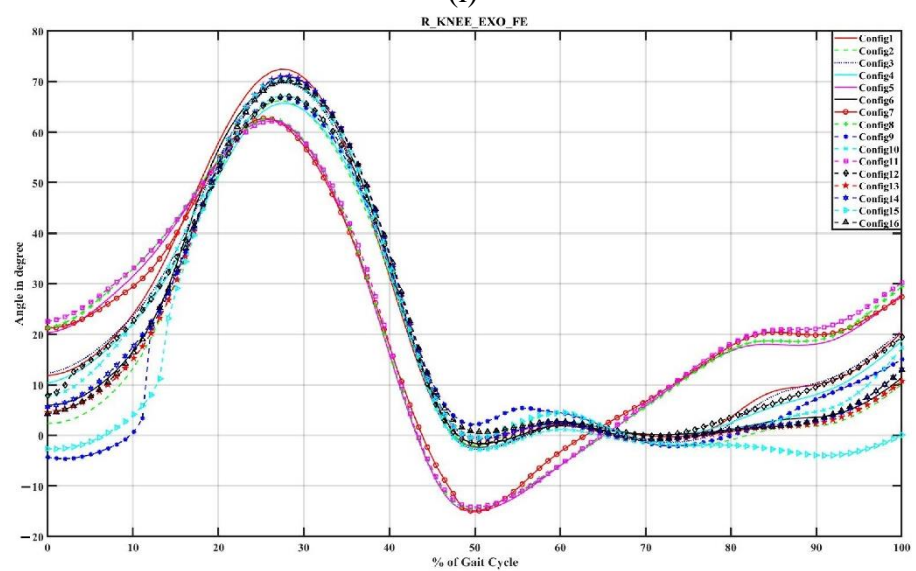
(k)



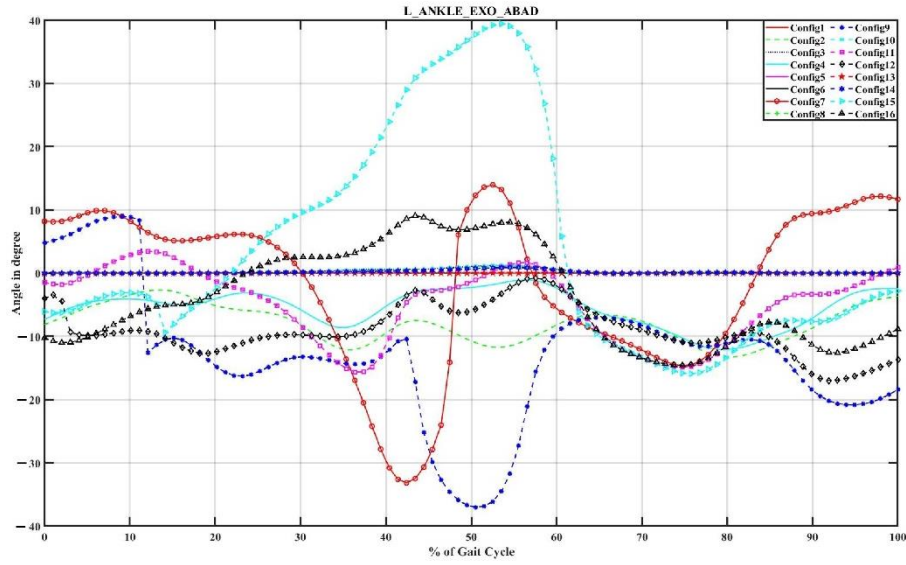
(l)



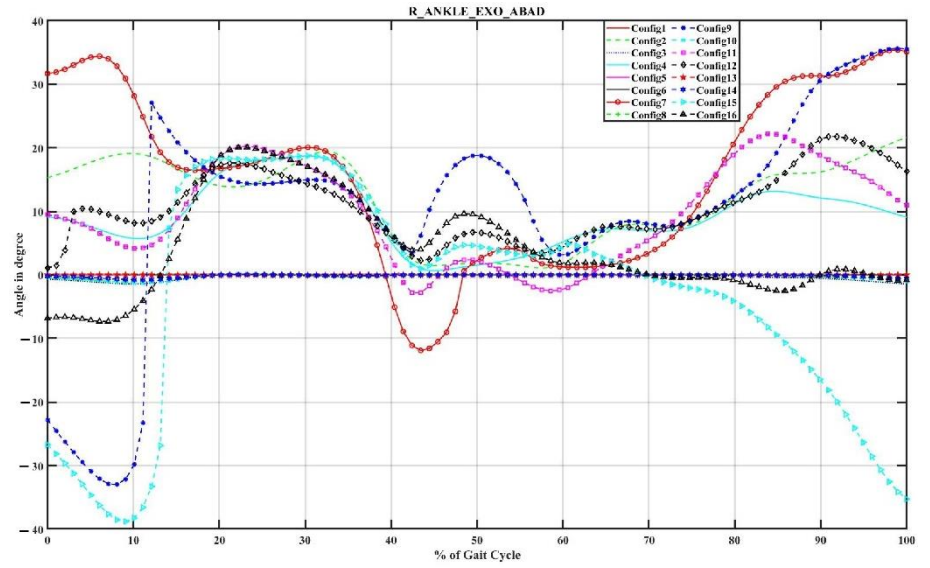
(m)



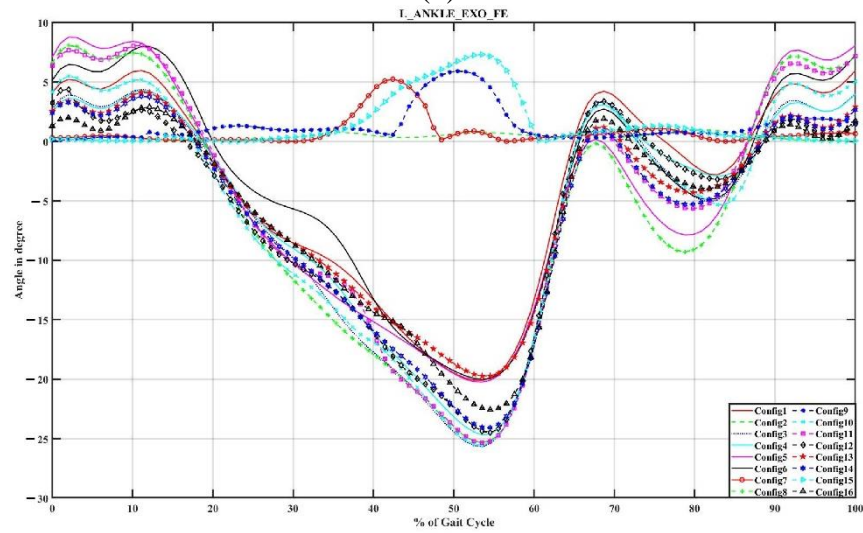
(n)



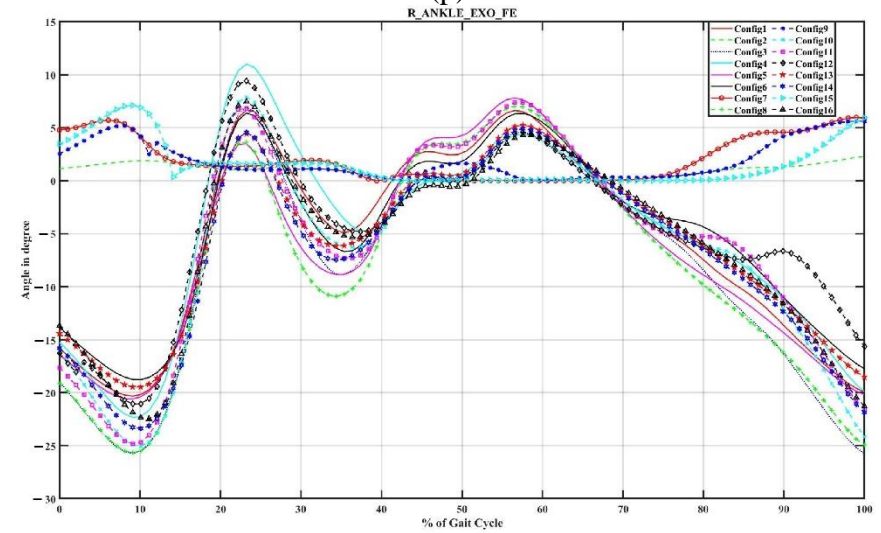
(o)



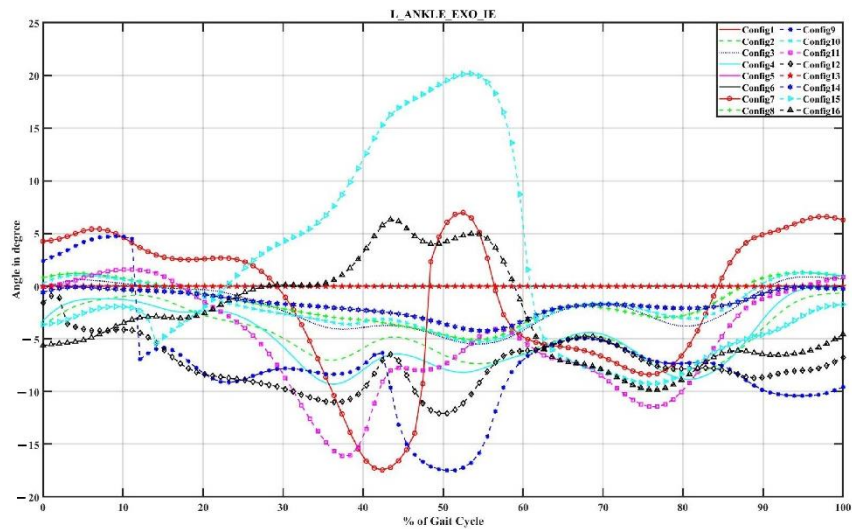
(p)



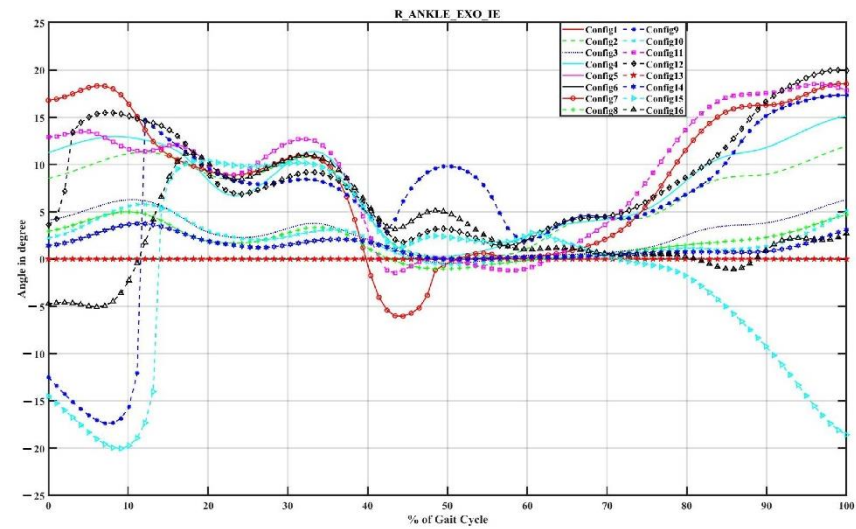
(q)



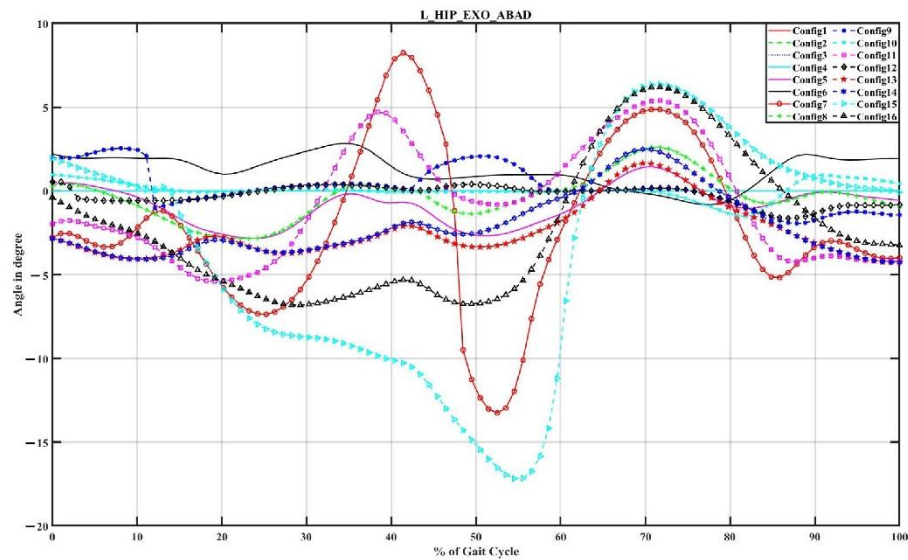
(r)



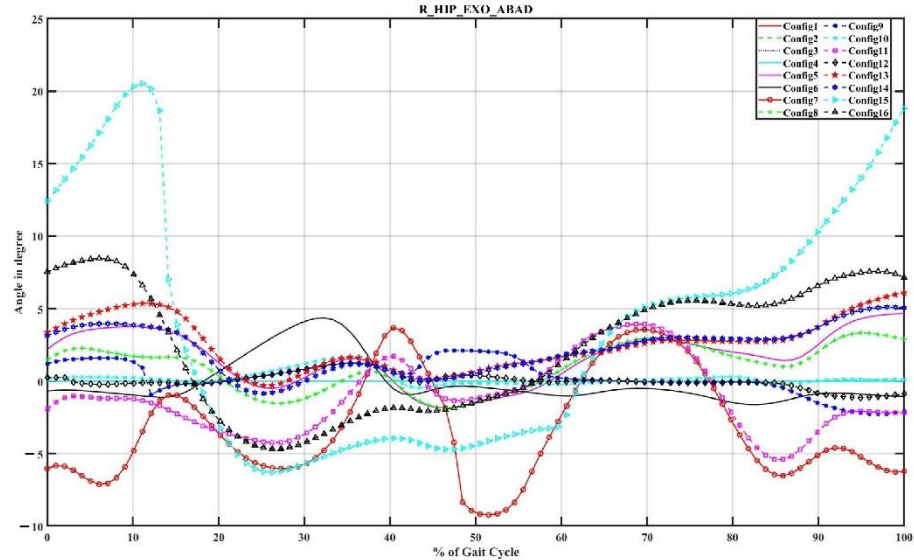
(s)



(t)



(u)



(v)

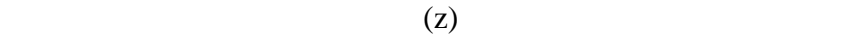
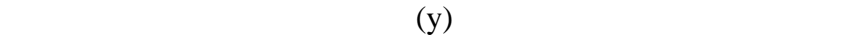
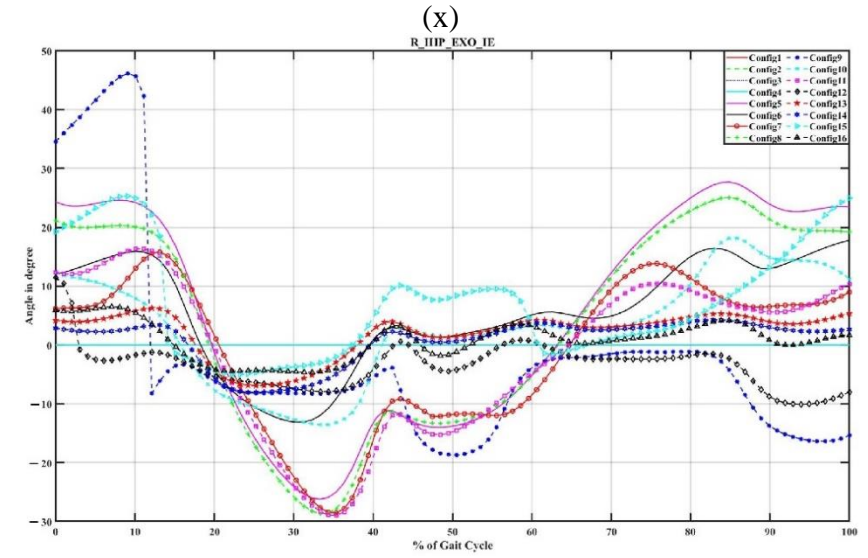
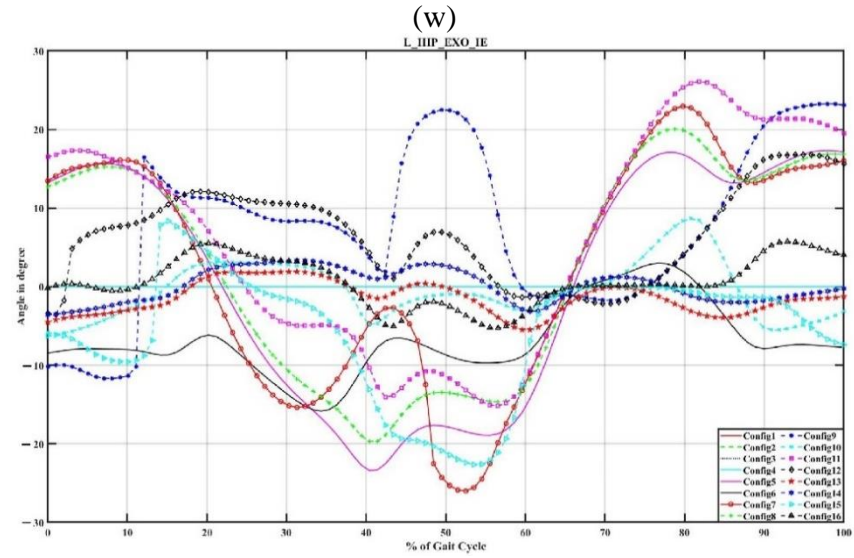
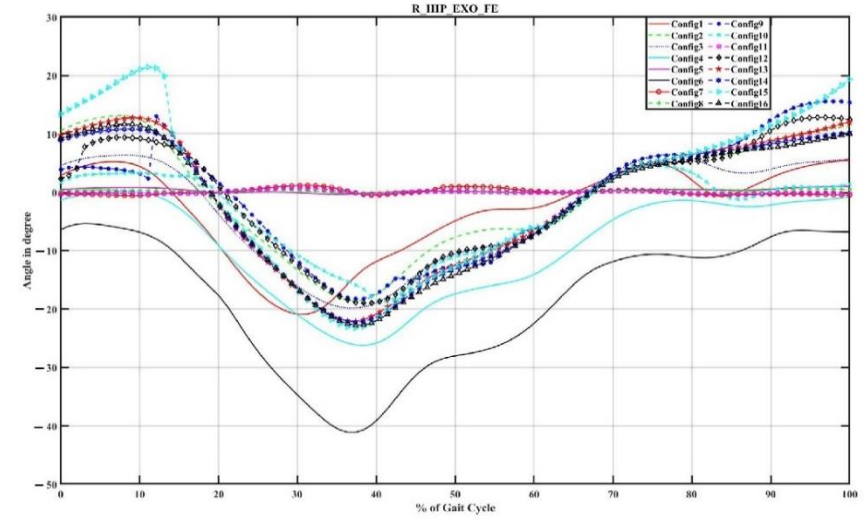
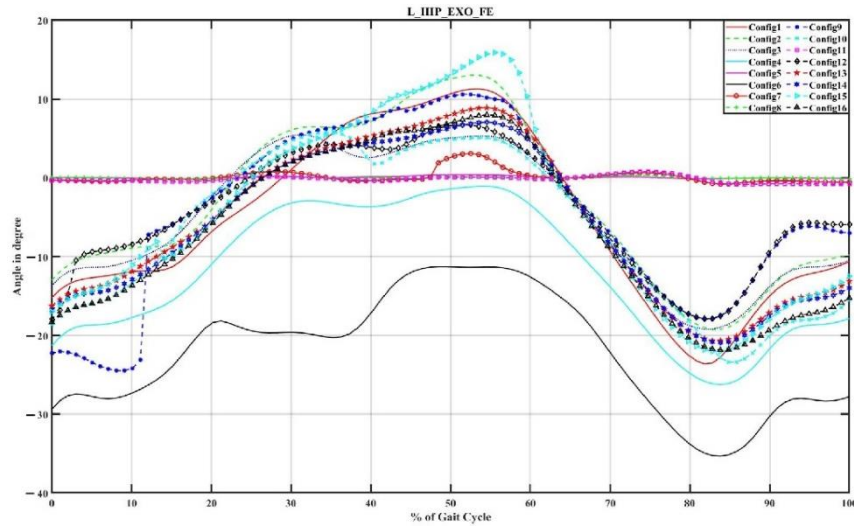
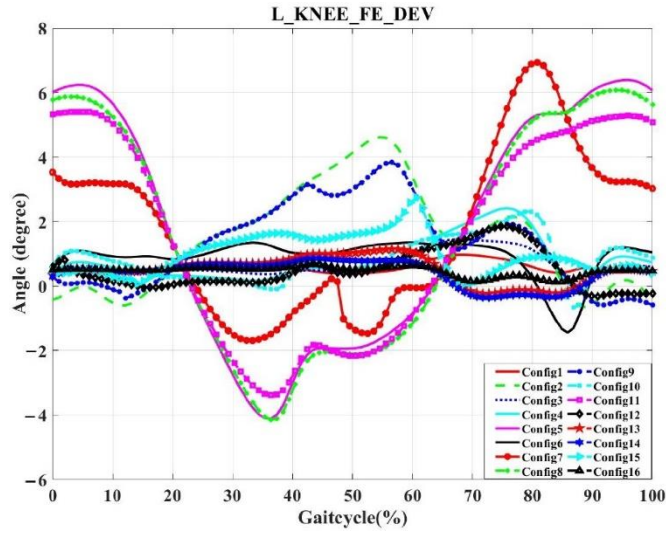
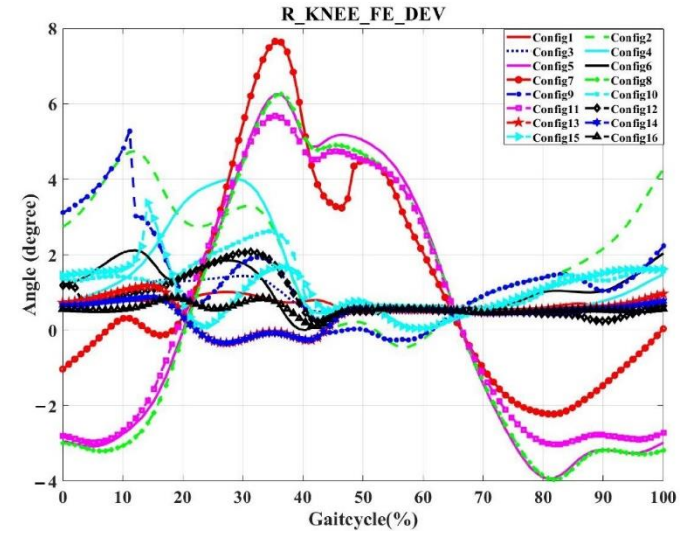


Figure S1: (c) –(f) and (g)–(l) presents the RoM of joint angles (Ankle and Hip) for human and figures (m)– (z) presents the RoM of joint angles (Hip, Knee and Ankle) for exoskeleton

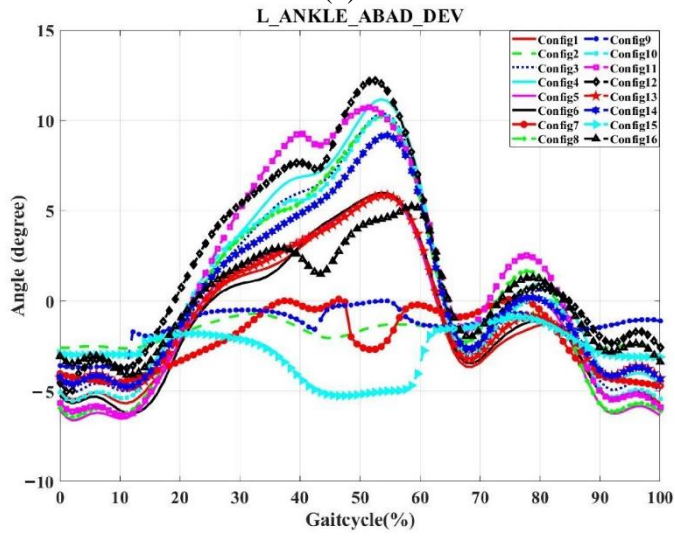
Deviation plots of the hip, knee and ankle joints between human and exoskeleton simulated for one gait cycle across all 16 configurations



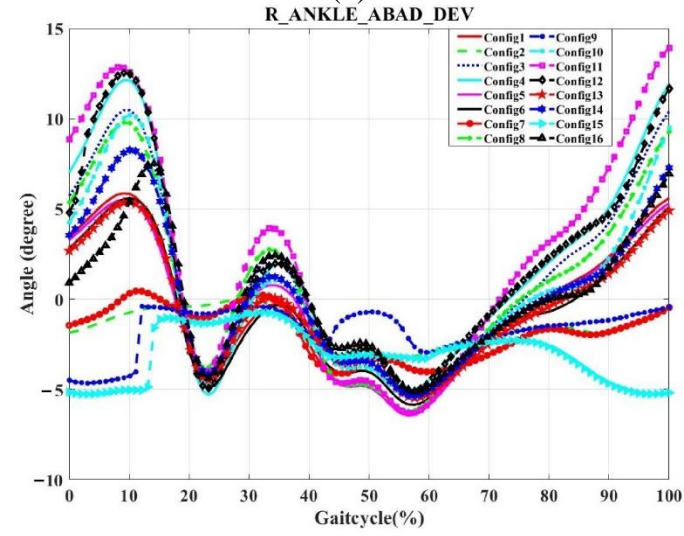
(a)



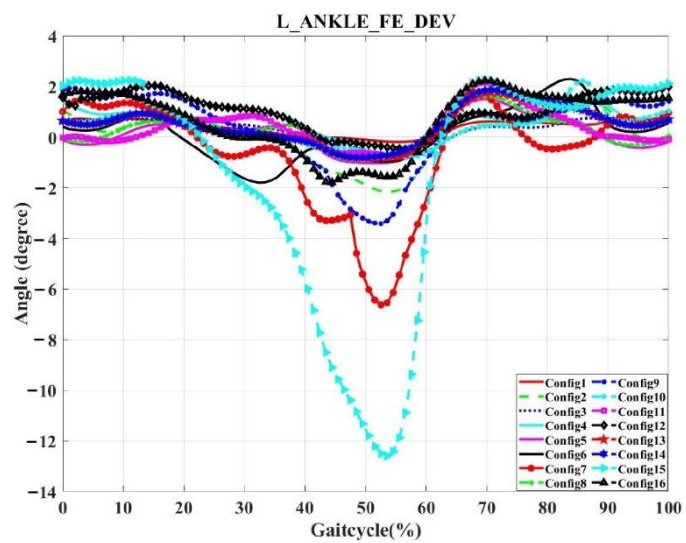
(b)



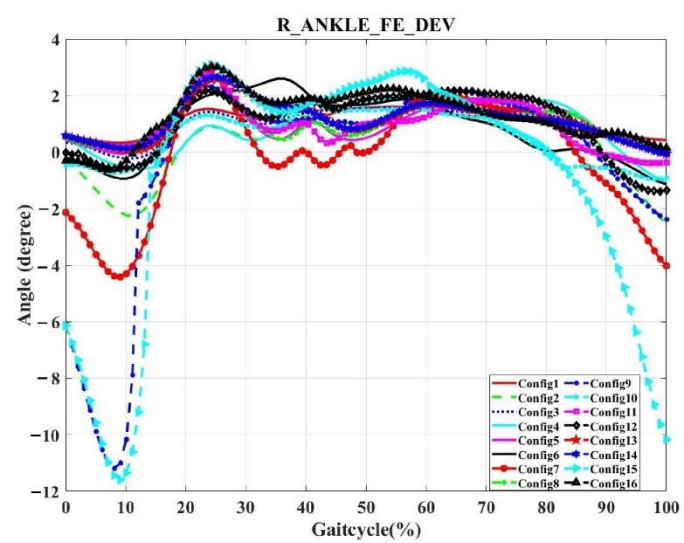
(c)



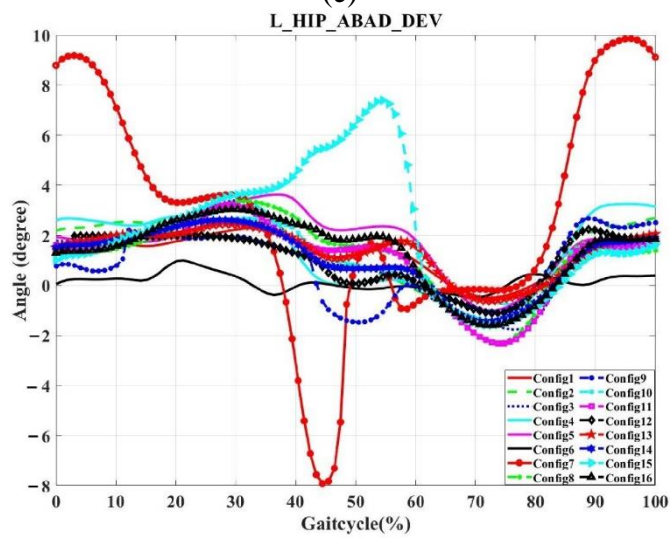
(d)



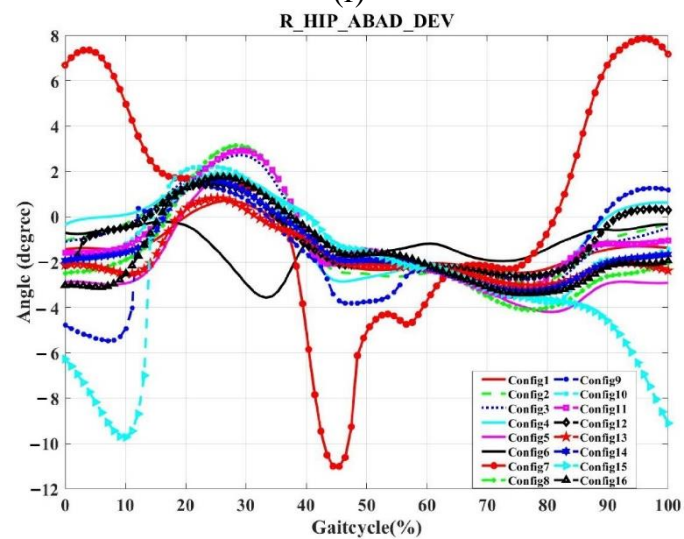
(e)



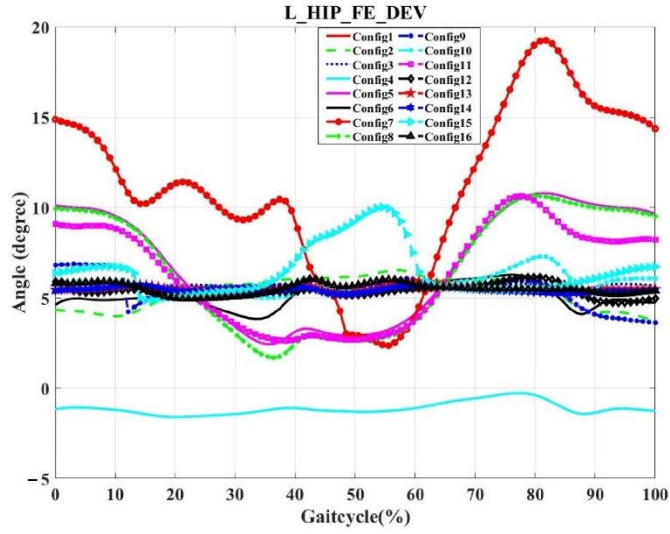
(f)



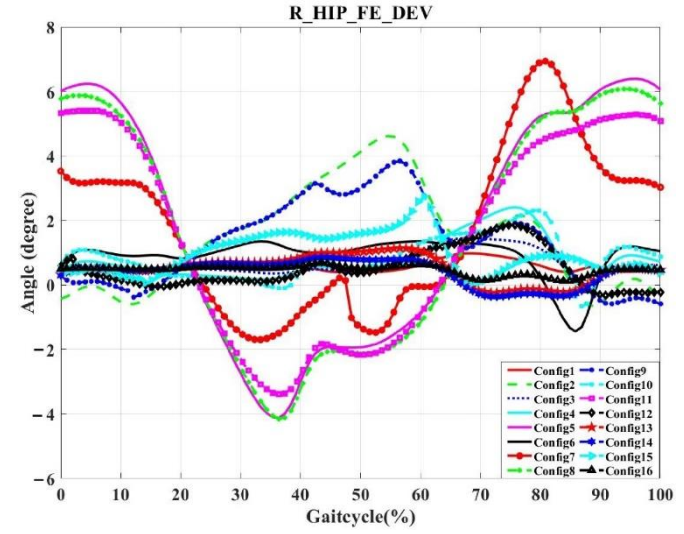
(g)



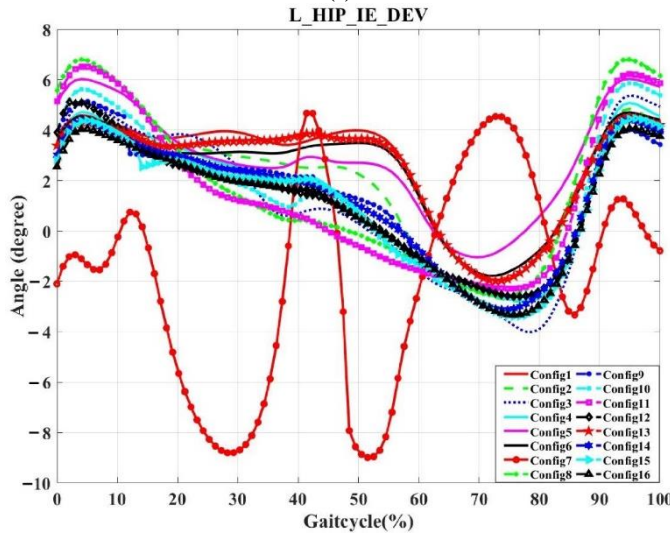
(h)



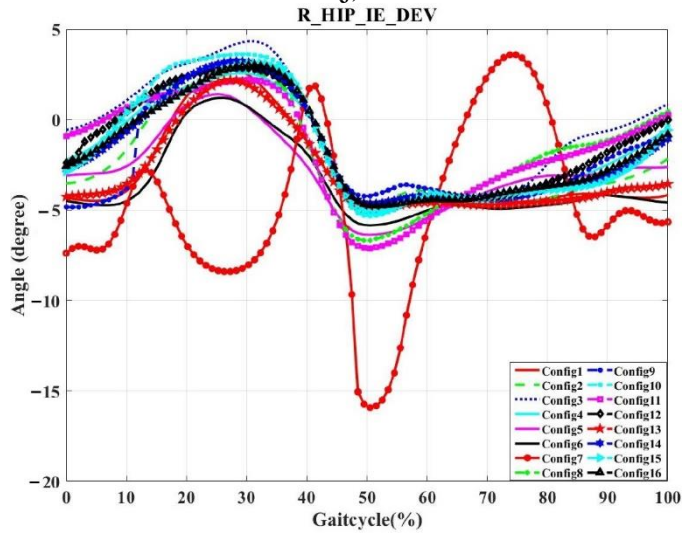
(i)



(j)



(k)



(l)

Figure S2: (a)–(l) presents the deviation of joint angles (Hip, Knee and Ankle) for all configurations

Deviation plots of the flexion-extension of hip, knee and ankle joints between human and exoskeleton during experimental validation.

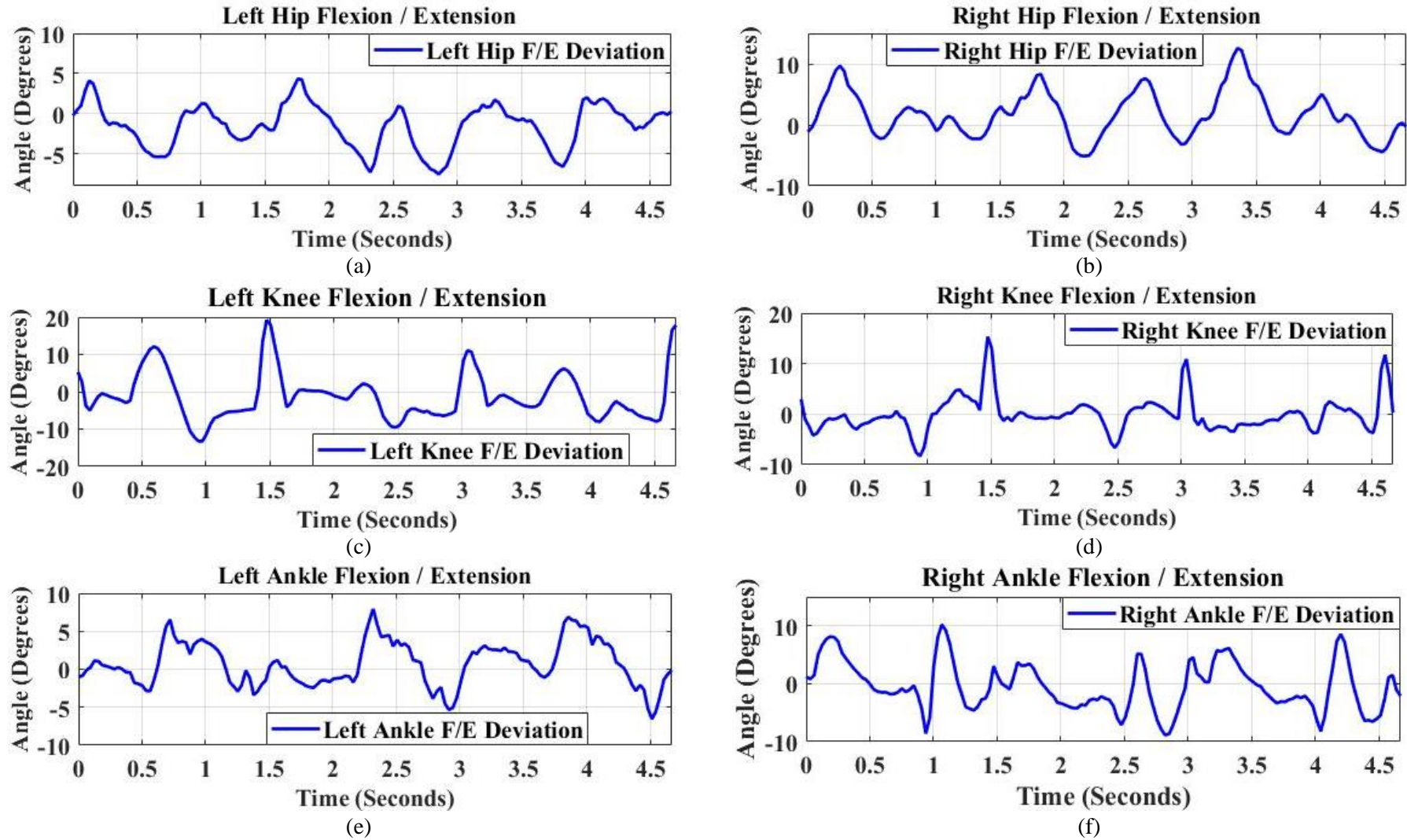


Figure S3: Deviation between human and exoskeleton flexion / extension at hip knee and ankle joints from experimental validation