

Contents

Acknowledgements	v
Abstract	vii
List of figures	xii
List of tables	xiv
1 Introduction	1
1.1 Exoskeletons: a solution?	1
1.2 Motivations	2
1.2.1 User-centered motivations	2
1.2.2 Science-driven motivations	3
1.2.3 Recommendations	5
1.3 Lean synthesis	5
1.4 Research questions	6
1.5 Organization of the thesis	7
2 Related Work	9
2.1 Hand-picked innovations	9
2.1.1 Model T	9
2.1.2 Swatch	9
2.1.3 Wheel stories	10
2.1.4 The Corsaire	10
2.1.5 Discussion	11
2.2 Genealogy of lean synthesis	11
2.2.1 Modularity	11
2.2.2 Axiomatic design	14
2.2.3 Lean manufacturing	14
2.2.4 Rapid prototyping and digital manufacturing	15
2.2.5 Mass customization	16
2.2.6 Platform products	16
2.3 Recent highlights in wearable robotics	16
2.3.1 New and noteworthy	17

2.3.2	Exoskeletons for individuals with motor-complete SCI	20
2.3.3	Exoskeletons for running	25
2.3.4	Partial hip orthoses for transfemoral amputees	26
2.3.5	Gait assessment exoskeletons	27
2.3.6	Modular exoskeletons	27
3	Lean Synthesis	29
3.1	Definitions	30
3.1.1	Module	30
3.1.2	Interface	30
3.1.3	Submodules	30
3.1.4	Input parameters	31
3.1.5	Output parameters	31
3.1.6	Standard and flexible parts	31
3.2	The Lean Synthesis Process	31
3.2.1	Use case	32
3.2.2	Translation	33
3.2.3	Prescription	33
3.2.4	Behavior	33
3.2.5	Composition	33
3.2.6	Formula	35
3.2.7	Validation	35
3.2.8	Flexible manufacturing	35
3.2.9	Mass manufacturing	36
3.2.10	Assembly	36
3.3	Principles (interpretation)	36
3.3.1	Information density	36
3.3.2	Depth pressure	36
3.3.3	Process parsimony	37
3.3.4	Uniqueness	37
3.4	Formula representations	37
3.4.1	Graphical representation	37
3.4.2	Markup language representation	37
3.5	Discussion	39
3.5.1	Filiation of lean synthesis	39
3.5.2	Differentiation from other frameworks	40
3.5.3	Expected properties of lean synthesis	41
3.5.4	Applicability	42
4	An implementation of lean synthesis for lower-limb exoskeletons	45
4.1	Standard modules	45
4.1.1	Joints	45
4.2	Flexible modules	48

4.2.1	DualSkin fabrication	48
4.2.2	DualSkin segments	50
4.2.3	Other modules	52
4.3	Submodules	56
4.3.1	DualSkin	56
4.3.2	Actuation	58
4.3.3	Electronics	58
5	TWIICE: A lower-limb exoskeleton for individuals with SCI	61
5.1	Synthesis	61
5.1.1	Use case	61
5.1.2	Behavior	62
5.1.3	Composition	63
5.1.4	Validation	66
5.2	Testing	67
5.2.1	Activities of daily living	68
5.2.2	Ambulation velocity	74
5.2.3	Usability and volume	78
5.2.4	Discussion	79
6	SPRIINT: A running exoskeleton for individuals with transfemoral amputation	83
6.1	Synthesis	83
6.1.1	Use case	83
6.1.2	Behavior	84
6.1.3	Composition	86
6.1.4	Validation	90
6.2	Testing	92
6.2.1	Mechanical characterization	92
6.2.2	User testing	98
6.2.3	Development schedule	101
6.2.4	Discussion	102
7	INSPIIRE: A passive exoskeleton for gait study	105
7.1	Synthesis	106
7.1.1	Use case	106
7.1.2	Behavior	107
7.1.3	Composition	107
7.1.4	Validation	108
7.2	Testing	108
7.2.1	Sagittally-constrained dynamic walking	108
7.2.2	A bio-inspired controller for low-actuator count standing balance	111
7.2.3	Discussion	116

8	WIITE: A ski-touring exoskeleton for individuals with SCI	119
8.1	Synthesis	120
8.1.1	Use case	120
8.1.2	Behavior	121
8.1.3	Composition	121
8.1.4	Validation	123
8.2	Testing	123
8.2.1	Preliminary testing	124
8.2.2	Project timeline	128
8.2.3	Discussion	129
9	DualSkin: A costing analysis	131
9.1	Design alternatives	131
9.1.1	DualSkin fabrication	132
9.1.2	CNC machining	132
9.1.3	Injection molding of fiber-reinforced thermoplastic	132
9.2	Costing model	133
9.3	Scenarii	133
9.4	Results	135
9.5	Discussion	136
9.6	Limitations	137
10	Discussion	139
10.0.1	Diversity	139
10.0.2	Perfomance	140
10.0.3	Efficiency	142
10.1	Conclusion	144
10.2	Limitations	145
10.2.1	Case studies	145
10.2.2	Thoroughness	145
10.2.3	Comparability	145
10.3	Future work	145
10.3.1	Automation and learning	146
10.3.2	Digital fabrication	146
10.3.3	In-depth testing	146
10.3.4	Dissemination	146
10.3.5	Diversity	147
	Bibliography	168
	Credits	171