

A Framework for Human-Exoskeleton Interaction Based on sEMG Interface and Electrotactile Feedback

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- Six-types motion intention is recognised by LSTM neural network based on sEMG of arms.
- The electrotactile is applied to feedback of five kinds states of exoskeleton and making up for the losing proprioception.
- Muscle fatigue of arms during use of exoskeleton is monitored and quantified with sEMG.

