Learning-Based Lower-Limb Joint Kinematic Estimation Using Open-Source IMU Data

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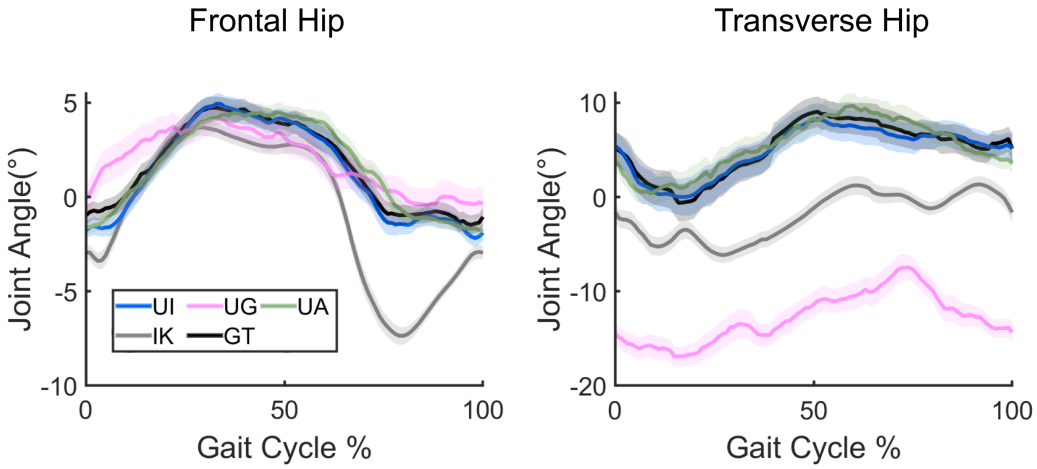
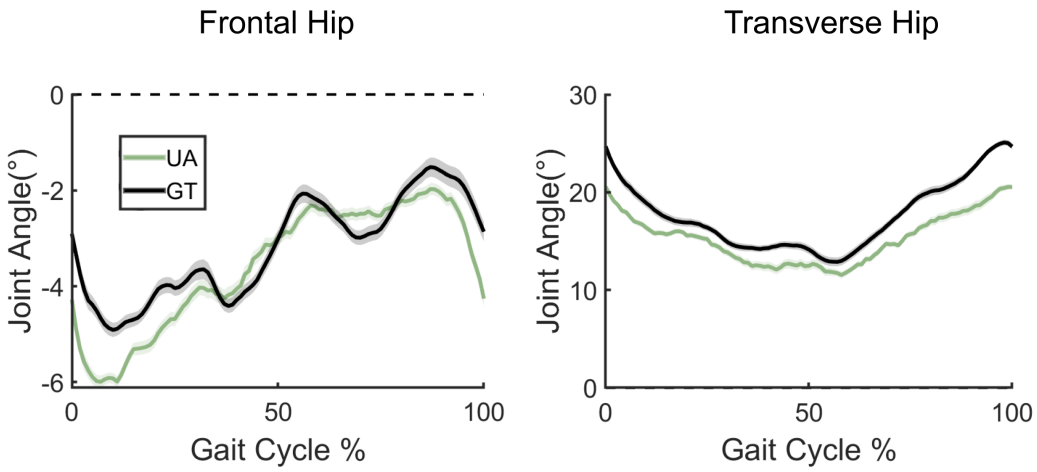
Supplementary information



Supplementary Figure 1. Average estimated frontal and transverse joint angles for the hip during the gait cycle, calculated using the LSTM architecture. IMU-IK is the IMU-based inverse kinematics, and GT is the ground truth from mocap-based inverse kinematics. The bands represent the standard error means.



Supplementary Figure 2. Average estimated frontal and transverse joint angles for the hip during the gait cycle, using the collected dataset. GT is the ground truth from mocap-based inverse kinematics. The bands represent the standard error means.