S5. Description of the orthoses' physical characteristics of inserted articles.

Author (s)	User Intent Modality (sensors type)	Limb assisted	Total DOF	Nº Ind. Actuators	Actuators types	Actuators input force	Actuators ext. torque/grip force	Power transmission
Delijorge et al., 2020	EEG sensor	Hand fingers	2	5	DC linear motor	-	-	Exoskeleton
Ren et al., 2019	sEMG and IMU	Shoulder and elbow	8	3	Servo motor	-	- Shoulder F: 4.785 Nm/ 1.937 Nm . - Shoulder E: 6.852 Nm/ 2.373 Nm .	Exoskeleton
Ha, Kim and Jo, 2018	Leap motion sensor and pressure sensor	5 hand fingers	2	5	Pneumatic	The PWM generated for driving the PNBA actuator was used to operate from 0 kPa to 89.63 kPa. considering actuator bending motion	-	Soft robotic
Wang et al., 2018	sEMG	Shoulder, elbow and wrist	3, being 1 passive and 2 actives	3	DC motors	-	- I = 0:079kgm^2. - Kv = 1.213N.s/rad.	End-effector

Zeng et al., 2018	sEMG sensor	Hand fingers	It has one DOF for F and E. As for the mechanism of the thumb, it has two DOFs for thumb rotation.	6	Microlinear	30 N	-	Cable-driven
Khan A, Khan F, Han, 2016	Load cells	Forearm and shoulder	3, being 2 active and 1 passive	2	DC motor	-	- Shoulder: 45 Nm; - Elbow: 25 Nm .	-
Agarwal, Fernandez and Deshpande, 2015	Magneto-resistive angle sensor	5 hand fingers	2	5	Bowden-cable -based series elastic	-	- MCP: from 0.1N to -0.1N, approximately. - PIP: from 0.05N to -0.05N	Exoskeleton
ng et al., 2015	Sensors not specified to measuring the level of force	5 hand fingers	2	5	-	-	-20 to 20N	Exoskeleton
Khan et al., 2015	MCS and load cells	Shoulder and elbow	7, being 2 actives and 5 passives	-	-	-	- Shoulder: 45 Nm . - Elbow: 25 Nm .	Exoskeleton
Ramirez, Alfaro and Chairez, 2015	sEMG	5 hand fingers	2	6	DC motors	-	-	Cable-driven
Kavya et al., 2015	sEMG sensor	Hand and forearm	4	-	Servo motor	-	-	-
Chen and Lau, 2015	Not specified, but kinematic analysis was done	Shoulder, elbow and wrist	5	5	DC servo motor	-	-	Rigid link

Loconsole et al., 2014	sEMG and 3-axis force sensors	Shoulder, elbow and wrist	5	4	-	-	-	Exoskeleton
Tang et al., 2014	sEMG	Elbow	2	2	Pneumatic	0.6 MPa	-	Carbon fiber bracer, metal link and nylon joint
Seki et al., 2011	sEMG	Elbow	2	1	DC motor	-	-	Exoskeleton
Zhang and Nakamura, 2006	EOG	Shoulder and elbow	5, being 3 active and 2 passive	2	Servo motor	0.5N	8N	End-effector

Abbreviations: DOF = Degree of Freedom; E = Extension; EEG = electroencephalography; EOG = Electrooculogram; F = Flexion; IMU = Inertial Measurement Unit; MCS = Muscle Circumference Sensor; MCP = Metacarpophalangeal; MPa= Megapascal; PNBA = Pneumatic Networks Bending Actuator; PWM = Pulse with Modulation; sEMG = Surface Electromyography; - = Not informed.