

This article and any supplementary material should be cited as follows: Wang H, Tsai C, Jeannis H, Chung C, Kelleher A, Grindle GG, Cooper RA. Stability analysis of electrical powered wheelchair-mounted robotic-assisted transfer device. J Rehabil Res Dev. 2014;51(5):XX-XX. <http://dx.doi.org/10.1682/JRRD.2013.11.0240>

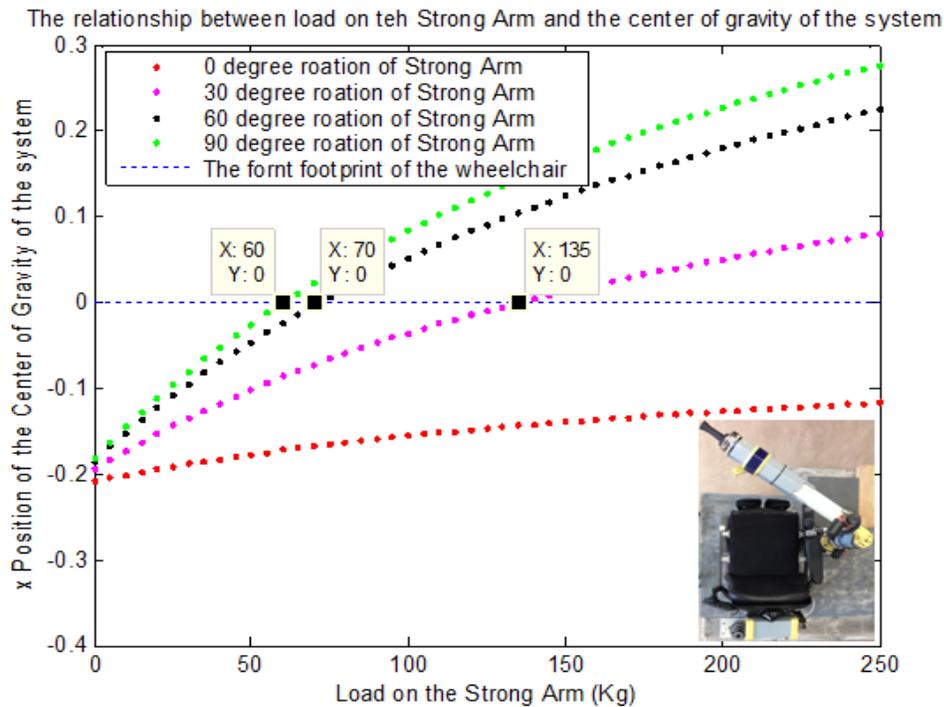


Figure A Left

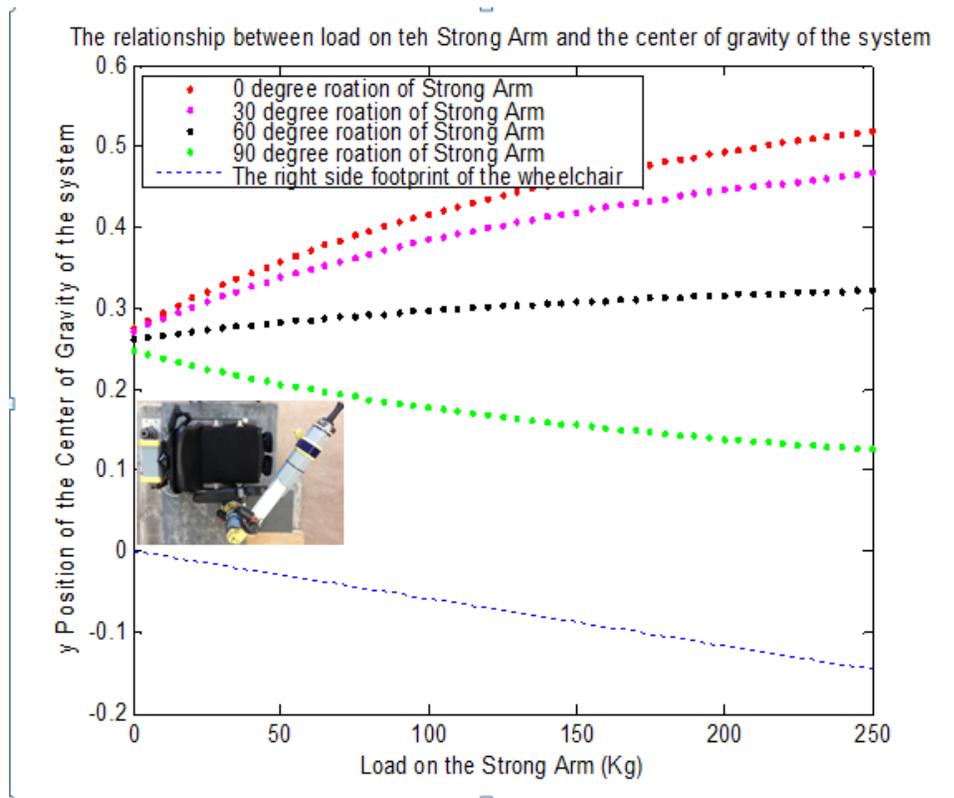


Figure A right

Fig. A. Center of gravity distribution for 4 different angles with variance loads on Strong Arm

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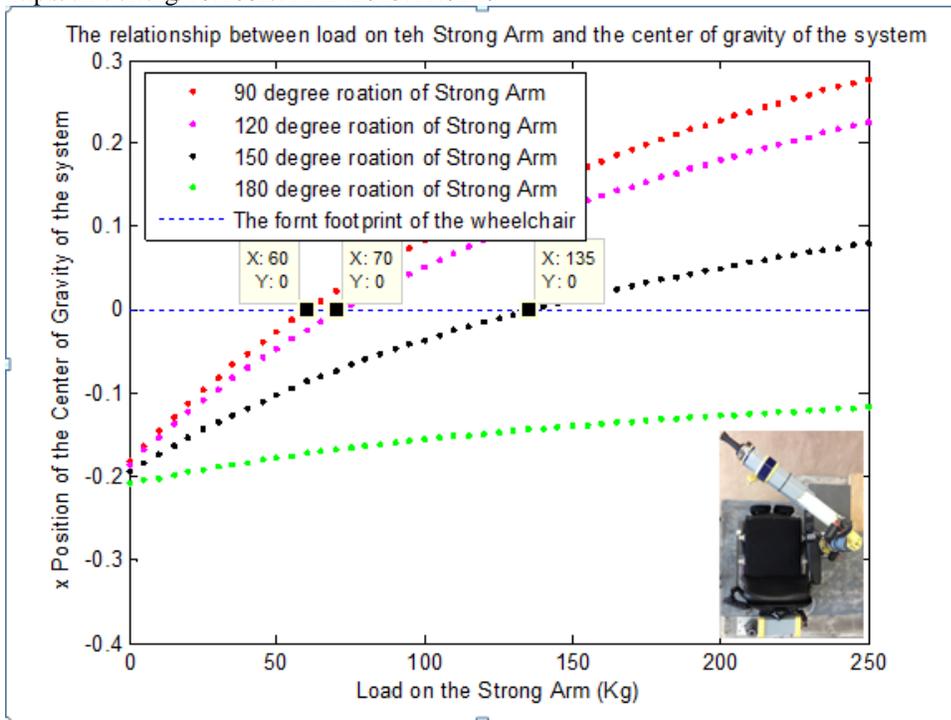


Figure B left

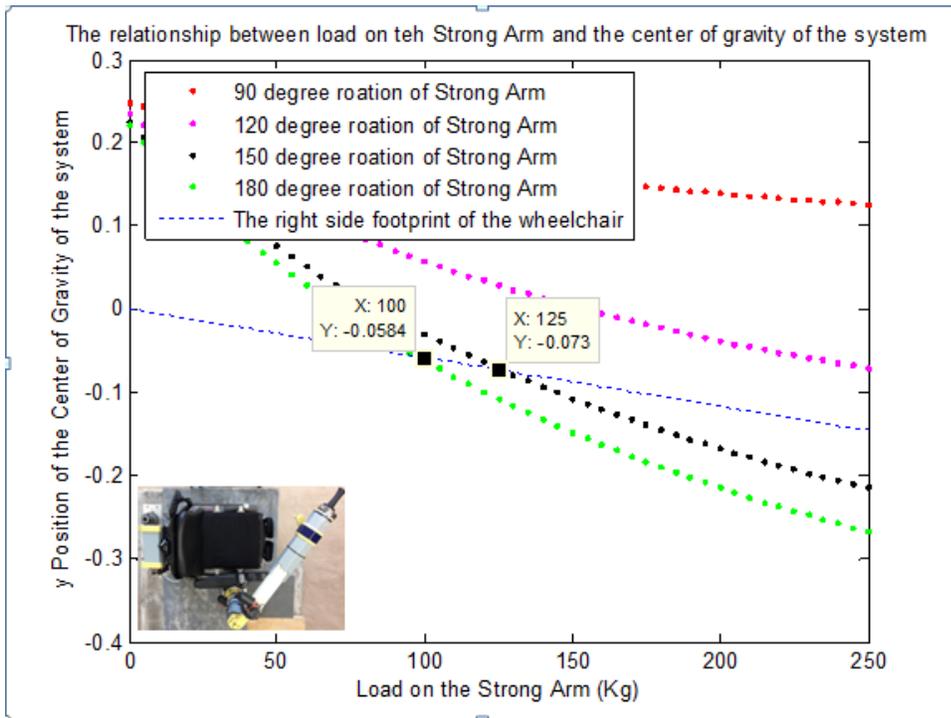


Figure B right

Fig. B. Center of gravity distribution for 4 different angles with variance loads on Strong Arm

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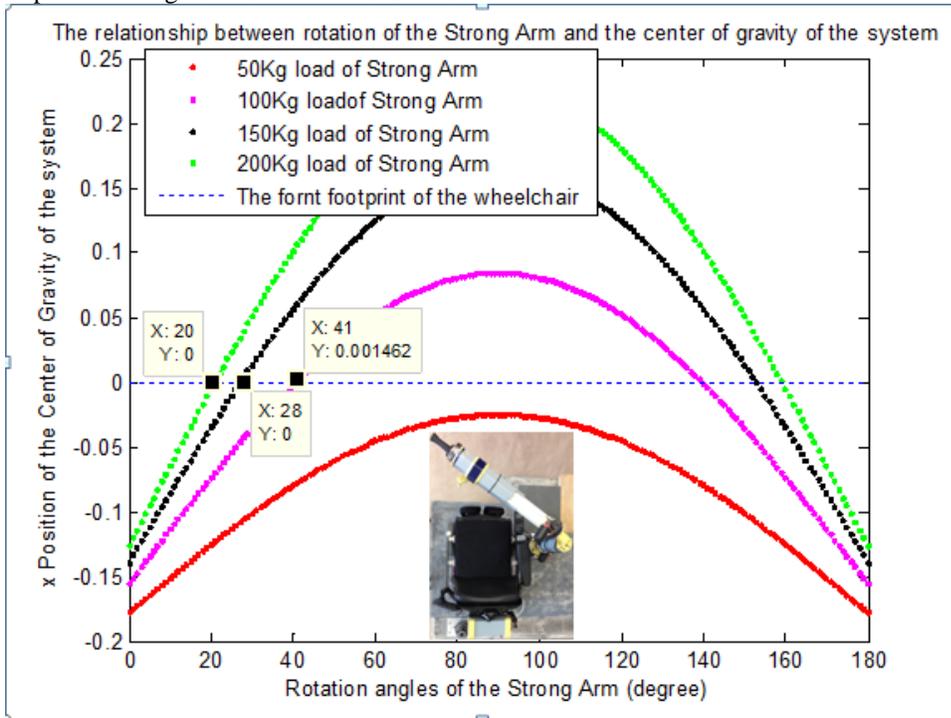


Figure C left

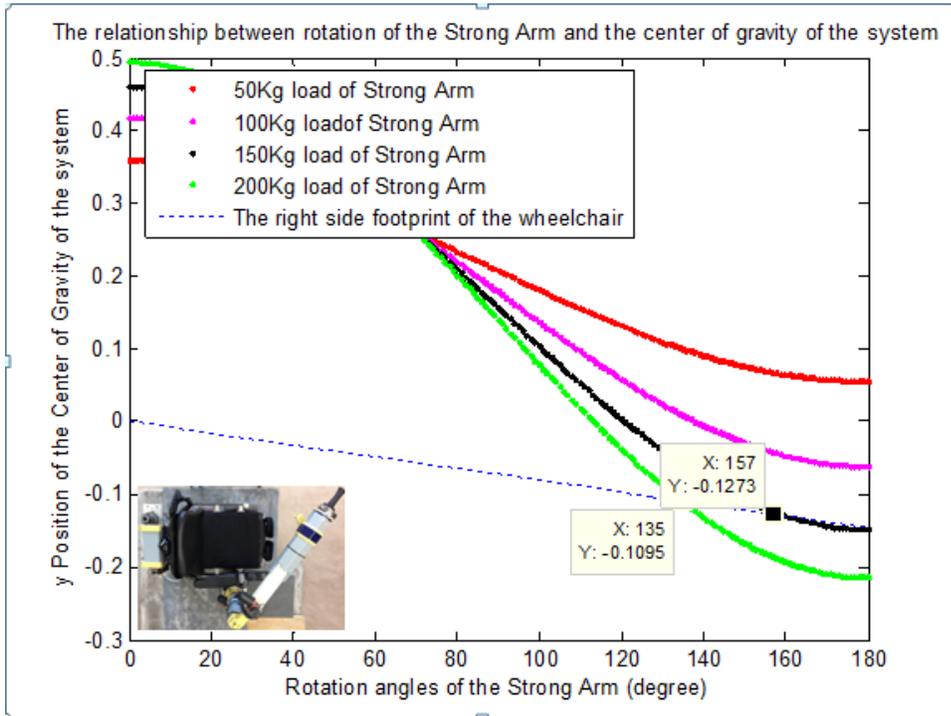


Figure C right

Fig. C. Center of gravity distribution for 4 different angles with variance loads on Strong Arm

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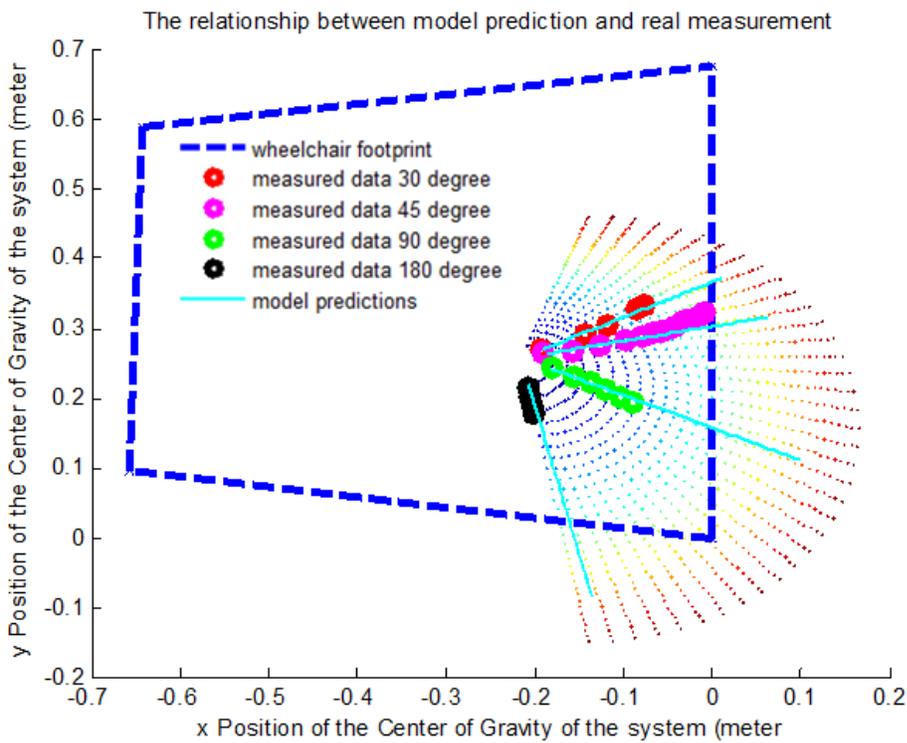


Fig. D. Center of gravity distribution for 4 different loads with variance rotation angles of Strong Arm

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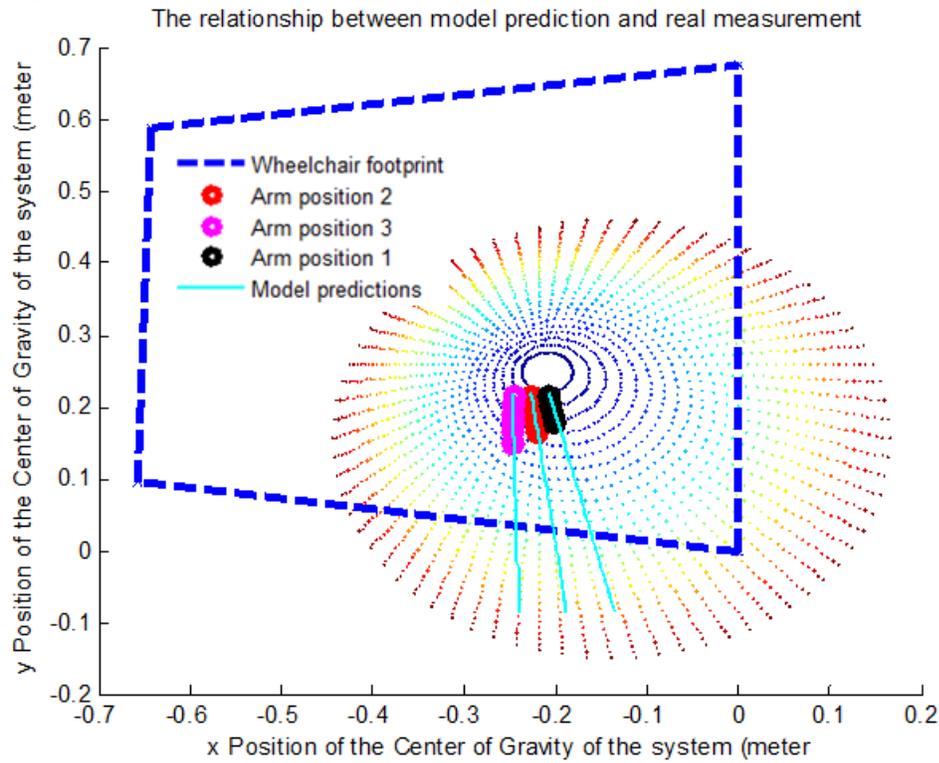


Fig. E. Center of gravity distribution for 3 different positions when arm rotated at 180 degree with variance loads

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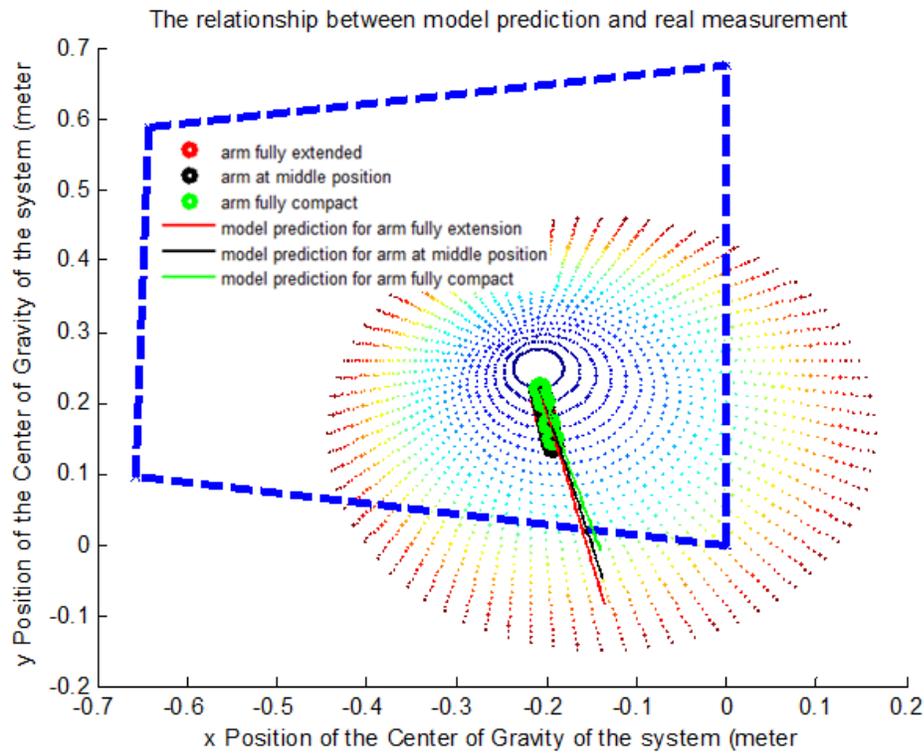


Fig. F. Center of gravity distribution when Strong Arm fully extended, at middle position and fully compact at 180 degree with variance loads

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Fig. G. The deformations of the Strong Arm due to load increases