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(54) **PORTABLE LOAD LIFTING SYSTEM**

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(57) **ABSTRACT**

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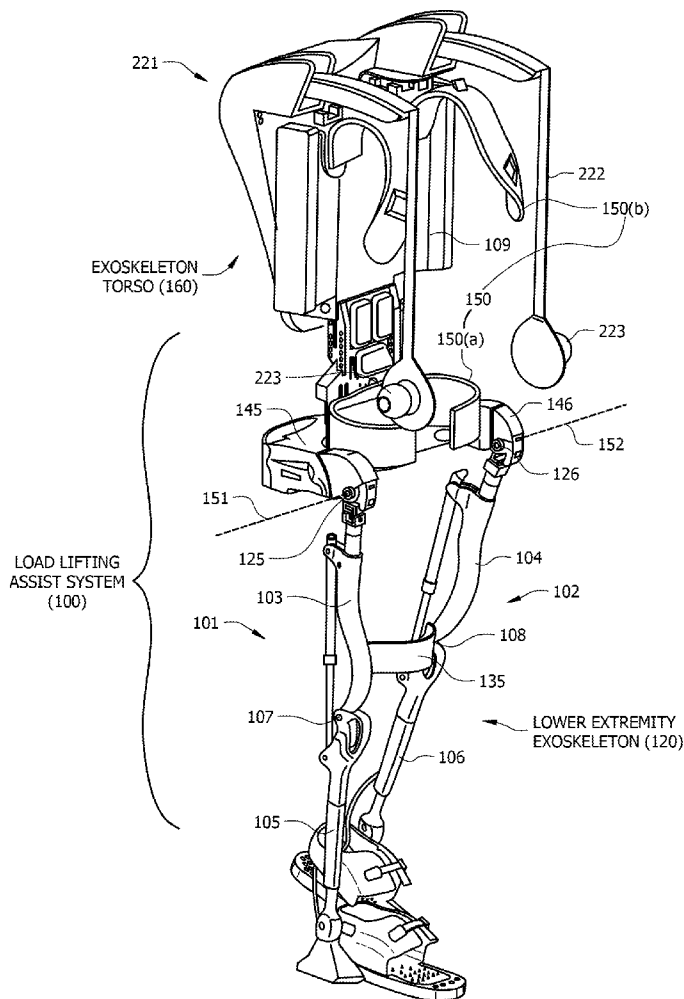
A portable load lifting assist system (100) includes a movable support structure including an exoskeleton torso (160) including an exoskeleton trunk (109) that is configured to be coupled to a person's upper body, and a load lifting mechanism (221) secured to the movable support structure including a winch (229) having a motor driven reel mechanism for reeling first and second lifting straps or cables (222) that are secured to first and second end effectors (223). First and second handles (224) are attached to an outside surface of the first and second end effectors, wherein the lifting straps or cables when driven by the winch lift a load contacted by the first and second end effectors. A lower extremity exoskeleton (120) is configured to be coupled to a person's lower limbs. The exoskeleton trunk couples to the person's upper body through an upper body interface device (150) that is coupled to the lower extremity exoskeleton.

Related U.S. Application Data

(60) Provisional application No. 61/322,684, filed on Apr. 9, 2010.

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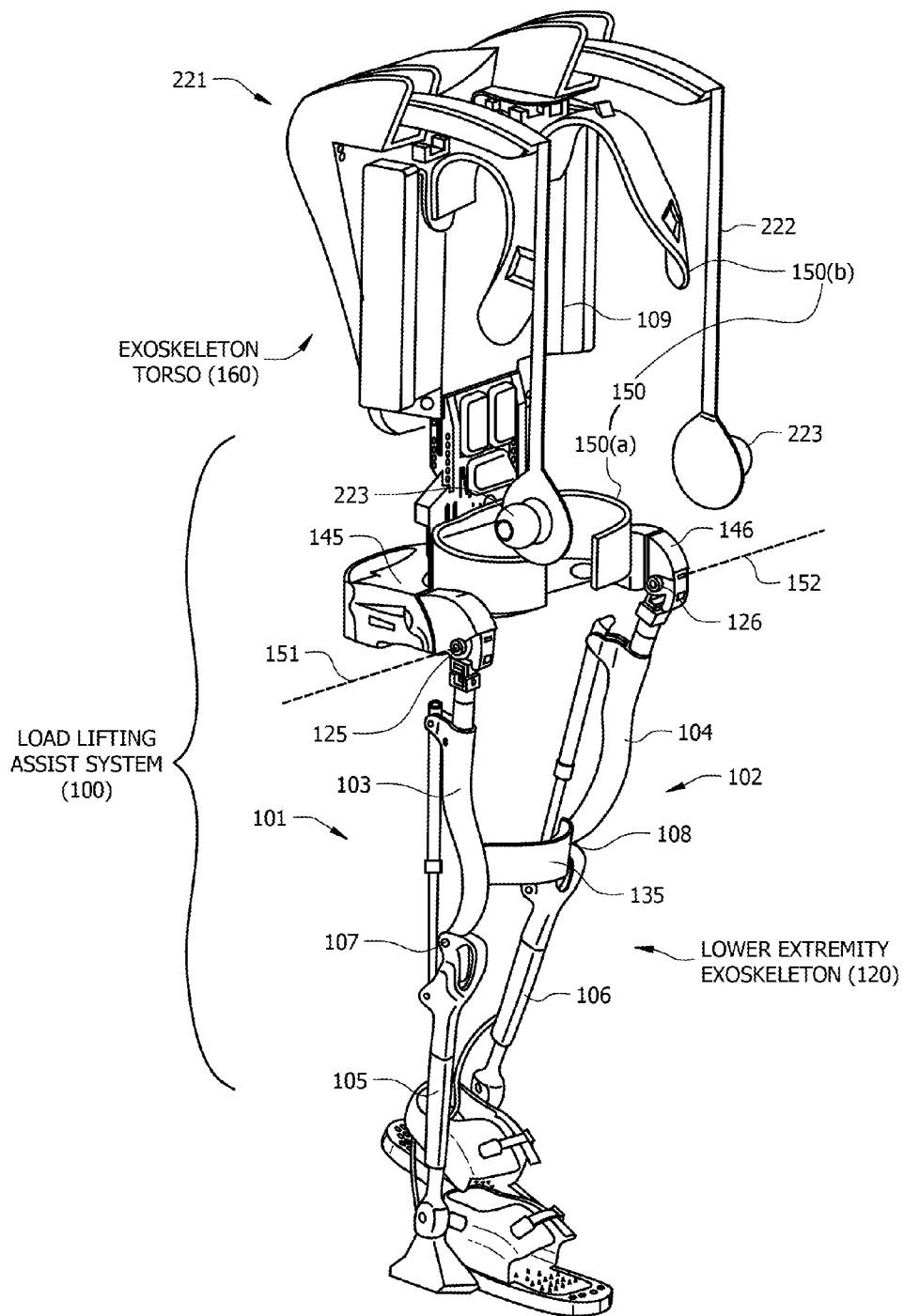


FIG. 1

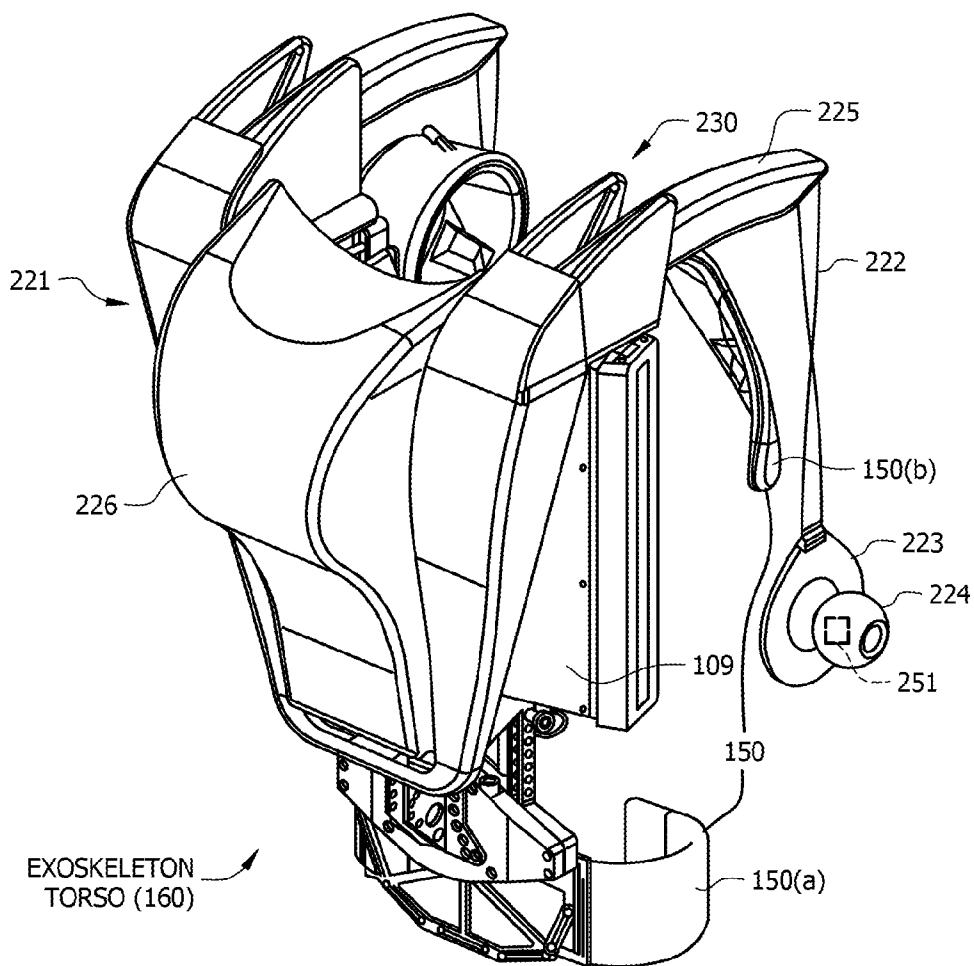


FIG. 2

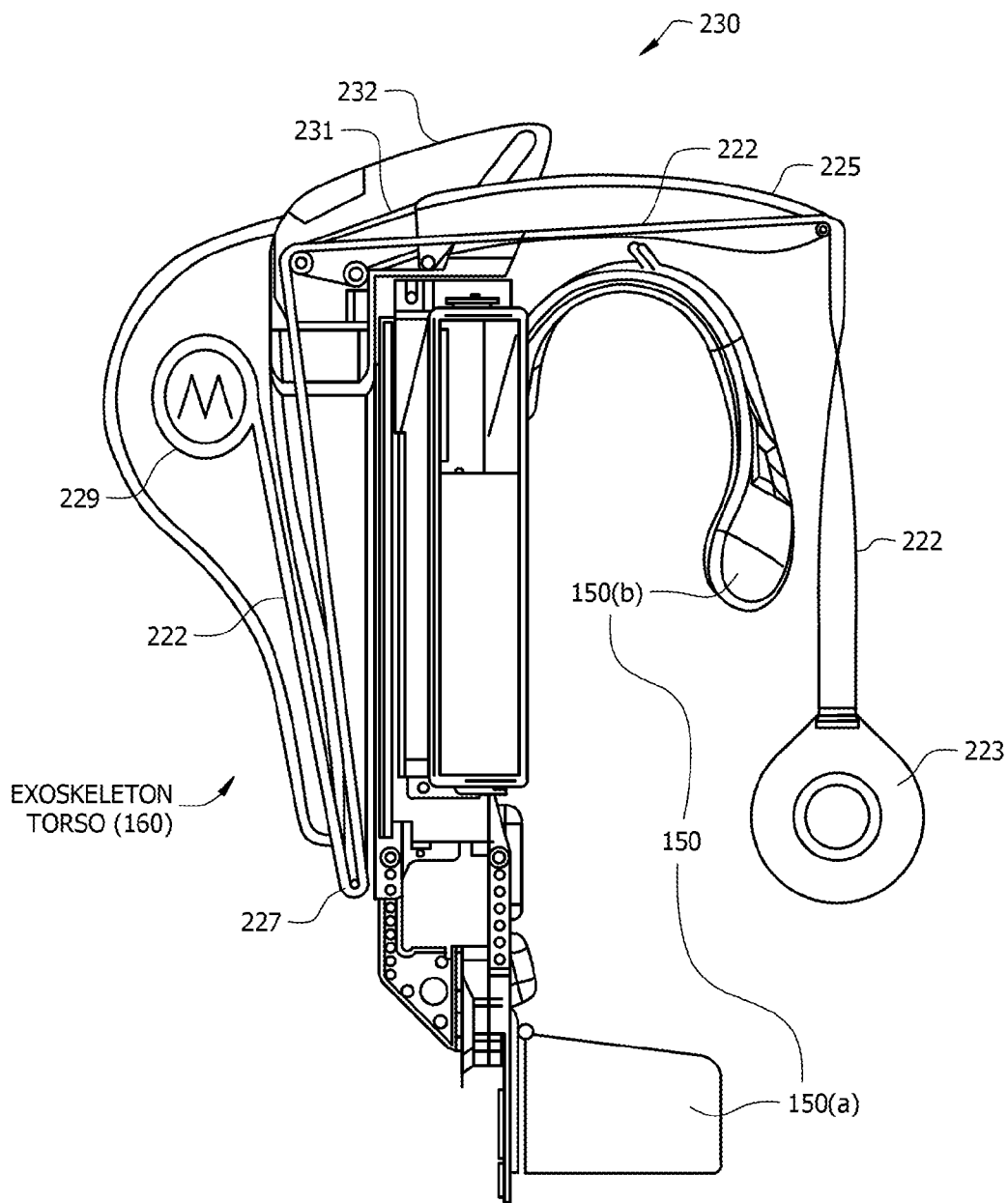


FIG. 3

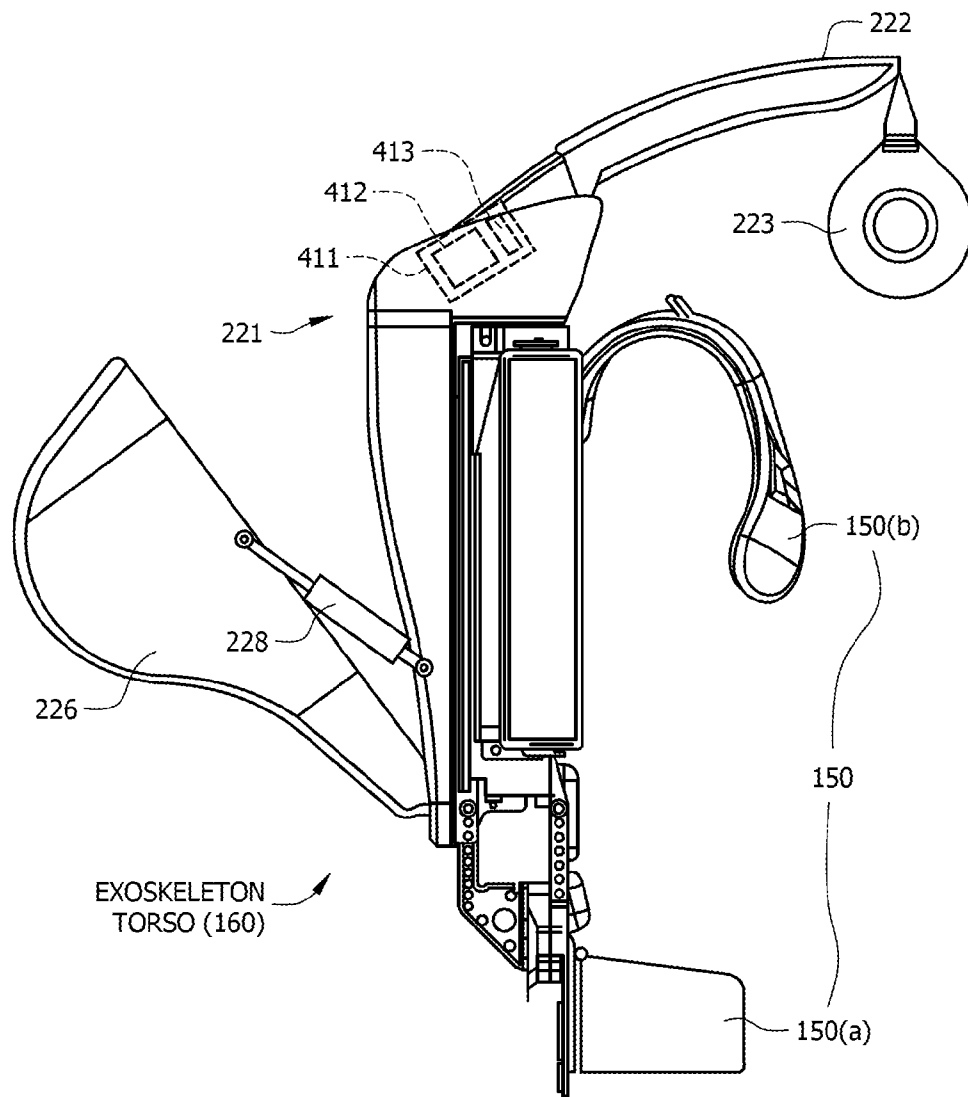


FIG. 4

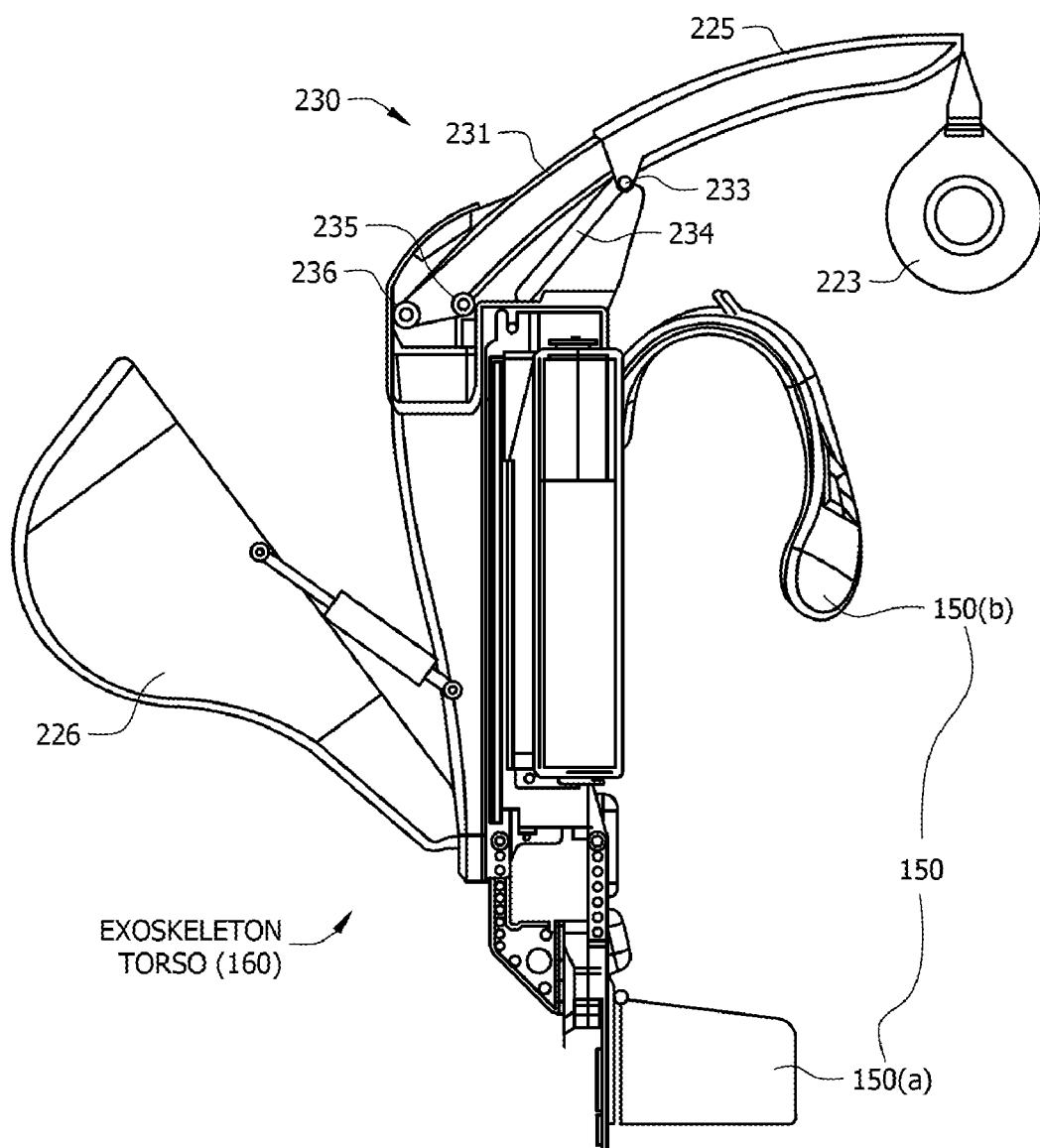


FIG. 5

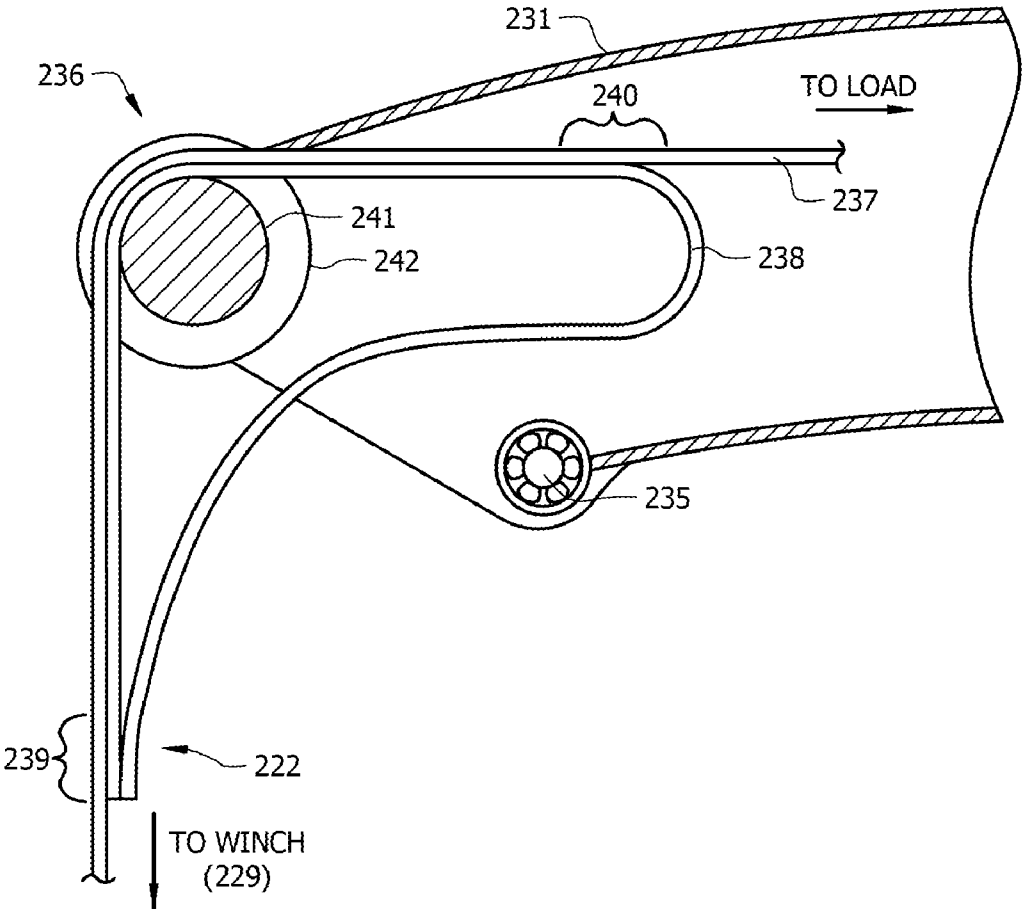


FIG. 6

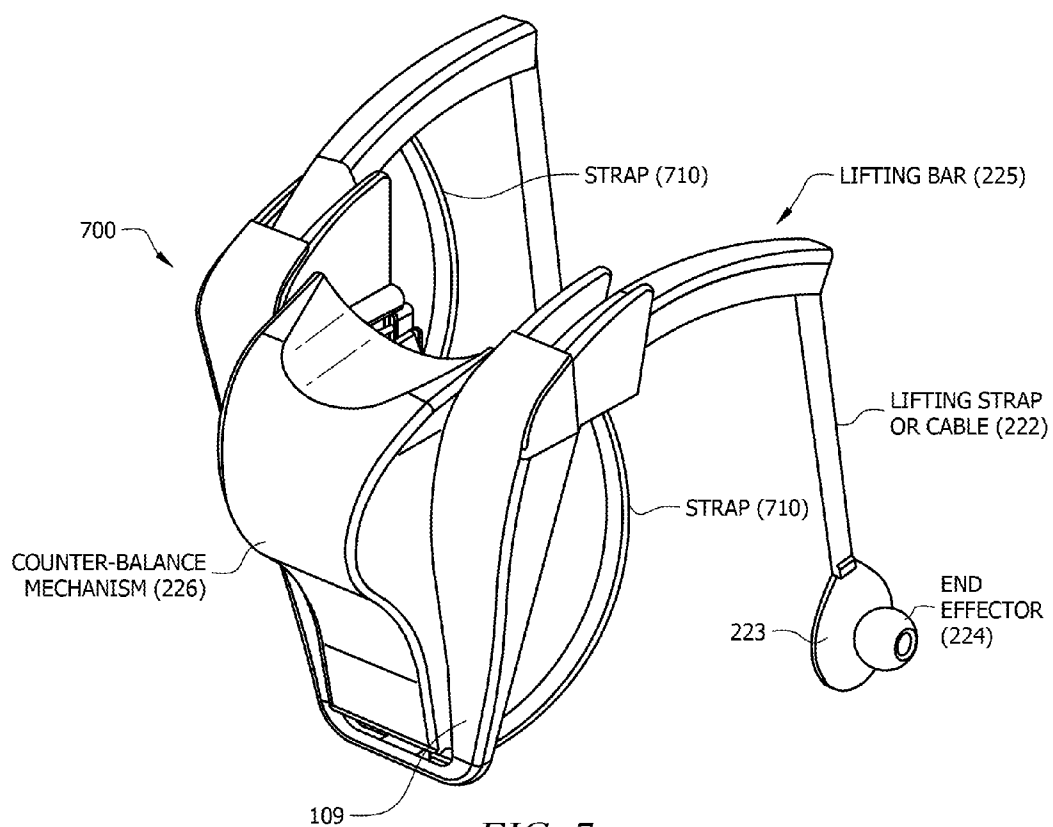


FIG. 7

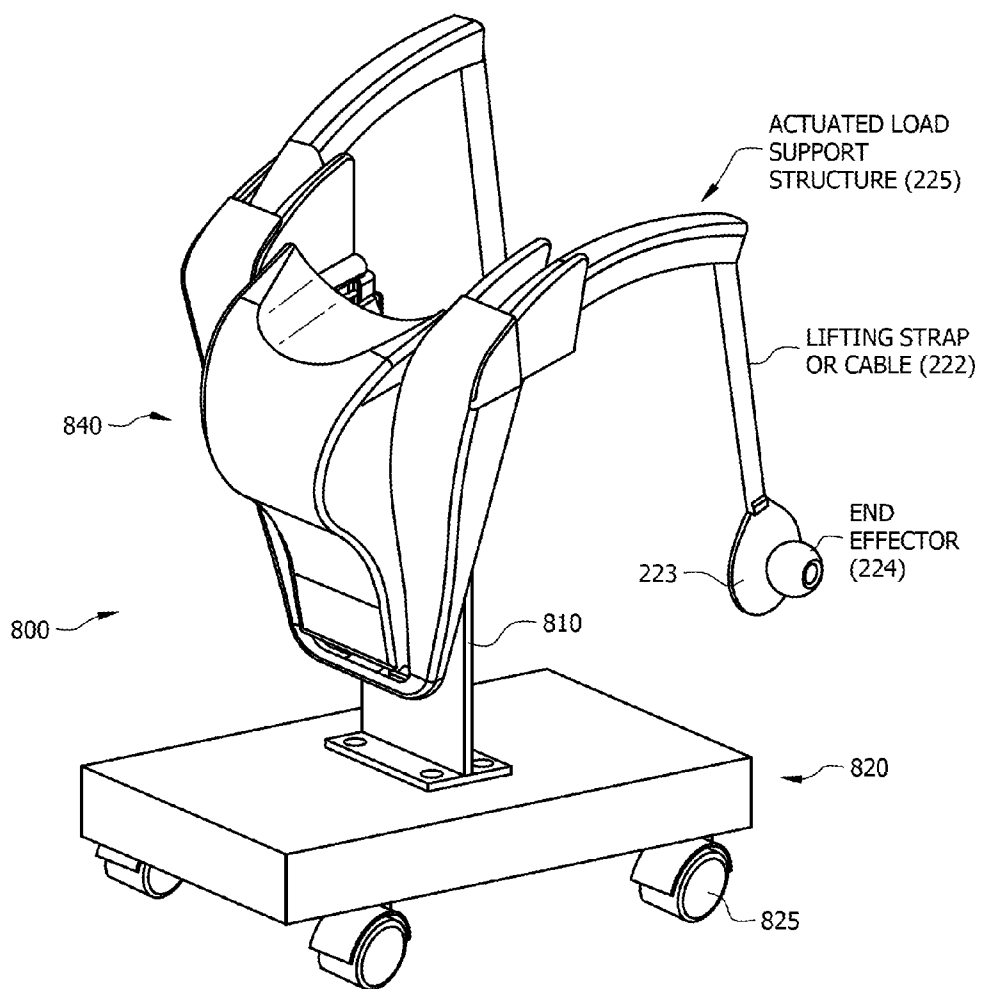


FIG. 8

PORTABLE LOAD LIFTING SYSTEM

CROSS REFERENCE TO RELATED APPLICATIONS

[0001] This application claims the benefit of Provisional Application Ser. No. 61/322,684 entitled "PORTABLE LOAD LIFTING ASSIST MECHANISM", filed Apr. 9, 2010, which is herein incorporated by reference in its entirety.

U.S. GOVERNMENT RIGHTS

[0002] The U.S. Government has certain rights to disclosed embodiments based on a contract between Lockheed Martin Corporation and the U.S. Army Natick Soldier Research Development and Engineering Center (NSRDEC).

FIELD

[0003] Disclosed embodiments relate to portable load lifting systems.

BACKGROUND

[0004] Certain jobs require individuals to repetitively lift and carry heavy loads. These activities significantly increase muscular-skeletal stress on the body, potentially leading to injuries, with some injuries potentially being permanent injuries.

[0005] One known load lifting assist system utilizes an exoskeleton which incorporates fully articulated arms to allow for upper body lift assist. These arms have a similar range of motion to the user's arms and require significant sensing and actuation to ensure the system tracks the user to avoid any discomfort. Additionally, loads can be carried by utilizing a fixed load attachment which supports the load on the user, but prohibits raising or lowering the load from the fixed attachment point.

[0006] Another known lifting assist system has a fixed load assist mechanism that is built into the infrastructure of a warehouse or other facility. Typically the lift assist mechanism in this system is permanently attached to a fixed overhead gantry. This arrangement is thus limited to use within a limited region of the warehouse or other facility.

SUMMARY

[0007] Disclosed embodiments include portable load lifting systems that provide powered assisted straps or cables coupled to end-effectors for lifting and carrying or moving heavy loads. In one embodiment, the portable load lifting system is a load lifting assist system that can be worn by a human user to transfer the weight of the load through the frame of the load lifting assist system to the ground or other lower surface (e.g., a floor). In this embodiment, loads attached to the load lifting assist system are carried by the exoskeleton, significantly reducing the load on the user, thus reducing the risk of muscular skeletal injuries and allowing more weight to be carried by the user.

[0008] Other embodiments disclosed herein include portable load lifting assist systems that are independent of a lower extremity exoskeleton. For example, the portable load lifting assist system can be worn like a backpack (e.g., secured by straps to a torso of a user). In another embodiment the portable load lifting system is operable without the need to

be secured to a human user, such including a mobile unit (e.g., a cart on wheels) that provides the system its support and portability.

[0009] Additionally, disclosed embodiments include portable load lifting assist systems that include structures that allow users to raise loads up to a minimum of shoulder height while still providing lift assistance. The power-assisted straps or cables enable a user to safely accomplish tasks that would typically require two or more personnel to carry the load. The end-effectors are quickly and easily exchanged to enable lift and carriage of many different items such as boxes, containers or munitions. Disclosed portable load lifting assist system embodiments allow for the normal lifting range of motion of a person, and through the use of disclosed shoulder lifting devices, allows the user to raise loads to shoulder height and above while still providing significant lift assistance.

[0010] Cantilevered weight can be used to keep the center of gravity close to the user to maintain balance and positive control of the load. Force sensors within the end-effectors can feed an onboard microprocessor-based controller to ensure system movement in concert with the user enabling accurate placement of objects that are lifted by the user. By detecting the force input by the user such as by including force sensors on the end effectors allows disclosed portable load lifting assist systems to also able to detect the user's intent (raise, lower or stabilize) and to provide the appropriate assistance to implement the user's intent via the lifting straps or cables attached to the end-effectors.

BRIEF DESCRIPTION OF THE DRAWINGS

[0011] FIG. 1 is a front view perspective drawing of an example portable load lifting assist system for aiding a human user comprising a lower extremity exoskeleton and exoskeleton torso, according to a disclosed embodiment.

[0012] FIG. 2 shows an example exoskeleton torso including the exoskeleton trunk with a load lifting mechanism connected to it, according to a disclosed embodiment.

[0013] FIG. 3 depicts a partial cross section depiction of an example load lifting bar mechanism, according to a disclosed embodiment.

[0014] FIG. 4 depicts the counterweight moved farther aft of the user in order to balance the load (at least partially) about the hip flexion-extension axes, which is useful in situations when loads in front of the user (on the end effectors) are high, according to a disclosed embodiment.

[0015] FIG. 5 depicts the position of lifting bar along the lifting bar guide being determined by the cam roller which is mounted on the lifting bar and moves in a slot on cam plate, wherein the lifting bar guide pivots on the pivot, and the pulley is a pulley over which the strap runs, according to a disclosed embodiment.

[0016] FIG. 6 is a close up view of the rear end of an example lifting bar guide, according to a disclosed embodiment.

[0017] FIG. 7 shows a depiction of an example portable load lifting assist system that includes lifting straps that allow the portable load lifting assist system to be worn like a backpack, according to another disclosed embodiment.

[0018] FIG. 8 shows an example portable load lifting system that comprises a cart including wheels that mounts the load lifting mechanism on a support structure that is secured to the cart, according to another disclosed embodiment.

DETAILED DESCRIPTION

[0019] Disclosed embodiments are described with reference to the attached figures, wherein like reference numerals, are used throughout the figures to designate similar or equivalent elements. The figures are not drawn to scale and they are provided merely to illustrate aspects disclosed herein. Several disclosed aspects are described below with reference to example applications for illustration. It should be understood that numerous specific details, relationships, and methods are set forth to provide a full understanding of the embodiments disclosed herein. One having ordinary skill in the relevant art, however, will readily recognize that the disclosed embodiments can be practiced without one or more of the specific details or with other methods. In other instances, well-known structures or operations are not shown in detail to avoid obscuring aspects disclosed herein. Disclosed embodiments are not limited by the illustrated ordering of acts or events, as some acts may occur in different orders and/or concurrently with other acts or events. Furthermore, not all illustrated acts or events are required to implement a methodology in accordance with this Disclosure.

[0020] Disclosed portable load lifting systems comprise a movable support structure and a load lifting mechanism secured to the movable support structure comprising a winch including a motor driven reel mechanism for reeling first and second lifting straps or cables that are secured to first and second end effectors. First and second handles are attached to an outside surface of the first and second end effectors, where the lifting straps or cables when driven by the winch lift a load contacted by the first and second end effectors. The portable load lifting system can comprise a load lifting assist system for aiding a human user that includes a lower extremity exoskeleton and an exoskeleton torso, or can be embodied in other disclosed embodiments to include an exoskeleton torso but not a lower extremity exoskeleton. Other disclosed embodiments comprise load lifting systems that are operable without the need to be secured to a human user.

[0021] In accordance with an example embodiment, FIG. 1 is a front view perspective drawing illustrating an example portable load lifting assist system **100** for aiding a human user comprising a lower extremity exoskeleton **120** and exoskeleton torso **160** including an exoskeleton trunk **109**. Portable load lifting assist system **100** is wearable by a person and allows its wearer to carry a load in his/her front, and aid the person when lifting an object by significantly reducing the load on the user. For example, portable load lifting assist system **100** can be used to help lift heavy loads while exerting minimal effort, such as in an example military application for soldiers going into combat with up to **130** pounds of combat gear.

[0022] Lower extremity exoskeleton **120**, in addition to other components, includes two leg supports, **101** and **102**, which are configured to be coupled to person's lower limbs and configured to rest on the ground or other surface (e.g., a floor) during their stance phase. The leg supports **101** and **102**, in addition to other components, include thigh links **103** and **104**, and shank links **105** and **106**. Two knee joints, **107** and **108**, are configured to allow flexion and extension between the shank links **105** and **106** and the thigh links **103** and **104** of the leg supports **101**, **102** during the corresponding leg support swing phase. However, the two knee joints **107** and **108** in some embodiments are configured to resist flexion

between the shank links **105** and **106** and the thigh links **103** and **104** of the leg supports **101**, **102** during the corresponding leg support stance phase.

[0023] Exoskeleton torso **160**, among other components, comprises an exoskeleton trunk **109**. Exoskeleton trunk **109**, among other components, comprises an upper body interface device **150**. Exoskeleton trunk **109** is configurable to be coupled to the person's upper body through the upper body interface device **150**. As used herein, a person's upper body refers to any location generally above the thighs including the buttocks of the person. Examples of upper body interface devices **150** comprise an element or combination of elements including, without limitation, vests, belts, straps, shoulder straps, chest straps, body cast, harness, and waist belts.

[0024] Exoskeleton trunk **109** is rotatably connectable to leg supports **101** and **102** at hip flexion-extension joints **125** and **126**, allowing for the hip flexion and extension rotations of leg supports **101** and **102** about hip flexion-extension axes **151** and **152** respectively. Leg supports **101** and **102** are configurable to be coupled to person's lower limbs through lower limb interface straps, with the lower right interface strap **135** shown in FIG. 1 (left lower limb interface strap not shown in FIG. 1 for clarity).

[0025] In some embodiments such as shown in FIG. 1, the respective lower limb interface straps are coupled to thigh links **103** and **104**. In some embodiments, lower limb interface straps are coupled to shank links **105** and **106**. In some other embodiments, lower limb interface straps are coupled to both the shank links and thigh links. Each lower limb interface strap can comprise an element or combination of elements including, without limitation, straps, bars, c-shaped brackets, body cast, and elastomers.

[0026] In operation, a person is coupled to (or wears) load lifting assist system **100** including exoskeleton torso **160** through upper body interface device **150** (a simple belt **150(a)** and shoulder straps **150(b)** shown in FIG. 1) and lower extremity exoskeleton **120** by coupling to two leg supports **101** and **102** through lower limb interface straps **135** and **136**. In some embodiments, lower extremity exoskeleton **120** among other things, may include two hip torque generators **145** and **146** which are configured to create torques between exoskeleton trunk **109** and leg supports **101** and **102**.

[0027] The exoskeleton torso **160** shown in FIG. 1 also includes a load lifting mechanism **221**. The load lifting mechanism **221** in FIG. 1 has within it a winch **229** (see FIG. 3) which includes a reel mechanism which can reel in straps or lifting cables **222** that in one particular embodiment are nylon straps in order to lift a load connected to or contacted by end effectors **223**.

[0028] Disclosed portable load lifting systems include a power source (not shown) that can comprise a battery source, or other power sources such as fuel cell-based power sources. Disclosed portable load lifting assist systems such as portable load lifting assist system **100** shown in FIG. 1 are also easy for a user to put on. The portable load lifting assist system **100** can arrive folded in a small package, so that soldiers or other users simply stretch out a leg and step into foot beds underneath the boot. Straps can then wrap around the thighs, waist and shoulders of the soldier or other user.

[0029] FIG. 2 shows an example exoskeleton torso **160** including the exoskeleton trunk **109** with a load lifting mechanism **221** connected to it, according to a disclosed embodiment. In FIG. 2, end effector **223** is shown as a simple paddle on which a high friction material is mounted on the

side opposite handle 224. The high friction material is used to help grip the sides of boxes and box like objects. One particular example of an example high friction material is "GECKO SKIN." However, end effector 223 may generally be any item used to lift a load and may contain a force sensor 251 in the handle 224 in order to measure the load force which the human user is putting on the handle. Item 225 is a lifting bar which (among other things) acts as a guide for cable 222. In one embodiment the load lifting mechanism 221 (including the internal winch, straps 222, end effectors 223, and handles 224) can be a mechanism sometimes referred to as a "human power amplifier." An example of such a "human power amplifier" is disclosed in U.S. Pat. No. 6,886,812 to Kazerooni.

[0030] The load lifting mechanism 221 can also include a movable counter weight 226 which may be rotated about counter weight rotation axis 227 (see FIG. 3) by a counter-weight actuator 228 (see FIG. 4). One advantageous aspect of this feature is to make the mass of the counterweight 228 include the mass of the winch 229 (including its motor, indicated by the "M" in FIG. 3). This can be done by routing the lifting strap or cable 222 through the path shown in FIG. 3. The strap or cable 222 passes over a pulley 236 which is concentric with the counter weight rotation axis 227 and therefore the motion of the counterweight 228 has very little affect on the length (or load) of the lifting strap or cable 222.

[0031] In one embodiment the motor can comprise a hydraulic motor. Hydraulic motor-based architectures can be highly energy efficient to help support battery powered operation of disclosed systems including the portable load lifting assist system 100 shown in FIG. 1.

[0032] In operation of the load lifting mechanism 221, when loads in front of the user (on the end effectors 223) are high, the counterweight 226 is moved farther aft of the user in order to balance the load (at least partially) about the hip flexion-extension axes 151 and 152. This is shown occurring in FIG. 4. This may be accomplished by using a controller 411 such as comprising a microprocessor (or microcomputer) 412 coupled to a force sensor 413 shown in FIG. 4 which measures the force being applied by load lifting mechanism 221 to the lifting strap or cable 222.

[0033] The controller 411 can then send a control signal that triggers movement of the movable counter weight 226 to a position appropriate to balance the moment created about hip flexion-extension axes 151 and 152 by the counter weight 226 with the moment created by the down force on the cables 222 due to the load in front of the user. One having ordinary skill in the art will note that there are many ways to measure the force in cables 222 and approximate the moment created by that force about hip flexion-extension axes 151 and 152. If this estimate were reasonable accurate and the net moment on the exoskeleton trunk 109 about hip flexion-extension axes 151 and 152 were to be near zero, the need for hip torque generators 145 and 146 may be greatly reduced or even eliminated because the wearer of the exoskeleton torso 160 can provide the small amount of remaining torque needed to the keep the exoskeleton trunk 109 upright.

[0034] One having ordinary skill in the art can construct a movable counter weight 226 which translated linearly or swung on a linkage type mechanism in a manner that would not be a rotation about a counter weight rotation axis 227. Any mechanism which will move the counterweight farther behind (or closer to) the hip flexion-extension axes 151 and 152 will generally be able to produce the desired effect.

[0035] FIG. 3 depicts a partial cross section depiction of an exemplary load lifting bar mechanism 230 associated with exoskeleton torso 160, according to a disclosed embodiment. The load lifting bar mechanism 230 includes a lifting bar 225, lifting bar guide 231, and cam plate 232. The lifting bar 225 slides over the lifting bar guide 231 in a telescopic fashion.

[0036] Referring to FIG. 5, the position of lifting bar 225 along the lifting bar guide 231 is determined by the cam roller 233 which is mounted on the lifting bar 225 and moves in a slot 234 on cam plate 232. The lifting bar guide 231 pivots on the pivot 235. Pulley 236 is a pulley over which the strap or cable 222 runs. When enough of the strap or cable 222 is retrieved such that the end effectors 223 are approaching the ends of the lifting bar 225, the lifting bar 225 starts to move upward and outward as the cam roller 233 moves upward in the slot 234 on cam plate 232.

[0037] To understand how the strap or cable 222 causes the lifting bar 225 to move upward and outward, FIG. 6 shows a close up view of the rear end of the lifting bar guide 231. In FIG. 6, it can be seen that the lifting strap 222 is actually comprised of two parts, the main lifting strap 237 and the lifting strap loop 238. The main strap 237 and the strap loop 238 are attached (e.g., sewn or bonded) together in the regions 239 and 240. Also, it can be seen that the pulley 236 comprises a body 241 and flanges 242. When the strap or cable 222 is pulled towards the winch 229, eventually the lifting strap loop 238 will wrap around the pulley body 241 and begin pulling downward on the pulley body. This will cause the lifting bar guide 231 to pivot on the pivot 235 which will cause the lifting bar 225 to move upward and outward. The strap loop 238 encounters the pulley body 241 at a point where there is still strap available between the end of the lifting bar 225 and the end effector 223. If there were no strap available, the lifting bar 225 could not extend along the lifting bar guide 231 because it would be constrained by the strap or cable 222.

[0038] One having ordinary skill in the art will note that there are many ways to construct a load lifting bar mechanism 230 which solely by pulling on a strap or a cable, the lifting bars will move upward and outward when the strap or cable is near the end of its travel. This allows the wearer of exoskeleton torso 160 to lift loads up to much higher heights than retracted lifting bars would allow.

[0039] In other disclosed embodiments, the portable load lifting assist system is not attached to a lower extremity exoskeleton 120 as described above relative to FIGS. 1-6. For example, the portable load lifting assist system can comprise only exoskeleton torso 160 which can be worn by a user analogous to a backpack.

[0040] FIG. 7 shows a depiction of an exemplary portable load lifting assist system 700 that includes straps 710 that allows the portable load lifting assist system 700 comprising exoskeleton trunk 109 to be worn by a user like a backpack. The movable counter weight 226 is identified in FIG. 7 by its function "counter-balance mechanism".

[0041] In yet another embodiment, the portable load lifting system can be attached to a mobile unit. FIG. 8 shows an exemplary portable load lifting system 800 that comprises a cart 820 including wheels 825 that mounts an example load lifting system 840 on a movable support structure 810 (e.g., bolted or welded) that is secured to the cart 820. The movable support structure 810 has mobility via the cart 820. Portable load lifting system 800 as well as disclosed portable load lifting assist systems can be used to support a variety of applications, including military, industrial and medical applications. assist soldiers during combat.

[0042] Advantages of disclosed portable load lifting systems include simplicity of actuation and flexibility to relocate to alternate work or other areas. Unlike a fully articulated arm, disclosed embodiments can use minimal sensing and actuation capability. This reduces the cost and power requirements and improves the reliability of the design as compared to an actuated arm. Also, unlike known fixed load attachment, load lifting systems disclosed herein allow for the raising and lowering of the load. For example, a user such as a soldier using a disclosed portable lifting assist system can raise a load above his or her shoulders, as well as lower the load to the ground.

[0043] Moreover, unlike known overhead lift devices integrated and thus fixed into the building infrastructure, portable load lifting systems disclosed herein have significantly enhanced flexibility in its usage. Because disclosed load lifting systems are not physically restrained to a work area, a user can operate the load lifting system inside a warehouse one minute, then head directly outside and continue to operate the load lifting system. This provides much greater utility to the user at lower cost and with lower power consumption.

[0044] While various disclosed embodiments have been described above, it should be understood that they have been presented by way of example only, and not as a limitation. Numerous changes to the disclosed embodiments can be made in accordance with the Disclosure herein without departing from the spirit or scope of this Disclosure. Thus, the breadth and scope of this Disclosure should not be limited by any of the above-described embodiments. Rather, the scope of this Disclosure should be defined in accordance with the following claims and their equivalents.

[0045] Although disclosed embodiments have been illustrated and described with respect to one or more implementations, equivalent alterations and modifications will occur to others skilled in the art upon the reading and understanding of this specification and the annexed drawings. While a particular feature may have been disclosed with respect to only one of several implementations, such a feature may be combined with one or more other features of the other implementations as may be desired and advantageous for any given or particular application.

I claim:

1. A portable load lifting system, comprising:
 - a movable support structure;
 - a load lifting mechanism secured to said movable support structure comprising a winch including a motor driven reel mechanism for reeling first and second lifting straps or cables that are secured to first and second end effectors, and
 - first and second handles attached to an outside surface of said first and second end effectors, wherein said straps or cables when driven by said winch lift a load contacted by said first and second end effectors.
2. The system of claim 1, wherein said movable support structure comprises an exoskeleton torso including an exoskeleton trunk that is configured to be coupled to a person's upper body through an upper body interface device.
3. The system of claim 2, wherein, wherein said upper body interface device comprises a vest, a belt, shoulder straps, chest straps, a body cast, harness, or a waist belt.
4. The system of claim 1, further comprising a first and a second force sensor in said first and second handles, wherein said first and second force sensors measure a load force which a person is putting on said first and second handles.

5. The system of claim 1, further comprising a lifting bar for guiding said lifting straps or cables.

6. The system of claim 1, further comprising a movable counter weight which is rotatable about a counter weight rotation axis by a counterweight actuator so that a mass of said counterweight includes a mass of said winch.

7. The system of claim 6, further comprising a controller including a microprocessor or microcomputer and a force sensor which measures a force being applied by said load lifting mechanism to said lifting straps or cables, wherein said controller is operable to send a control signal that controls a position of said movable counter weight to a position appropriate to balance a moment created about hip flexion-extension axes by the counter weight with a moment created by the down force on said lifting straps or cables in front of a person.

8. The system of claim 1, further comprising a load lifting bar mechanism comprising a first and a second lifting bar, which exclusively by pulling said lifting straps or cable, said first and said second lifting bar will move upward and outward when said lifting straps or cable is near an end of its travel.

9. The system of claim 8, further comprising a lifting bar guide, and cam plate, wherein said lifting bar slides over said lifting bar guide in a telescopic fashion, and

a position of said lifting bar along the lifting bar guide is determined by a cam roller which is mounted on said lifting bar and moves in a slot on said cam plate, said lifting bar guide pivoting on a pivot, and

a pulley over which said lifting straps or cables runs, wherein when enough of said lifting straps or cables is retrieved such that said first and second effectors are approaching ends of said lifting bar, said lifting bar starts to move upward and outward as said cam roller moves upward in said slot on said cam plate.

10. The system of claim 1, wherein said movable support structure is mounted on a mobile unit.

11. The system of claim 10, wherein said mobile unit includes wheels.

12. The system of claim 1, further comprising a lower extremity exoskeleton configured to be coupled to a person's lower limbs, wherein said movable support structure comprises an exoskeleton torso including an exoskeleton trunk that is configured to be coupled to an upper body of said person through an upper body interface device that is coupled to said lower extremity exoskeleton.

13. The system of claim 12, wherein said lower extremity exoskeleton comprises leg supports, and said exoskeleton trunk is rotatably connectable to said leg supports at hip flexion-extension joints for hip flexion and extension rotations of leg supports about hip flexion-extension axes.

14. The system of claim 1, wherein said motor comprise a hydraulic motor.

15. A portable load lifting assist system, comprising:

a movable support structure comprising an exoskeleton torso including an exoskeleton trunk that is configured to be coupled to a person's upper body;

a load lifting mechanism secured to said movable support structure comprising a winch including a motor driven reel mechanism for reeling first and second lifting straps or cables that are secured to first and second end effectors;

first and second handles attached to an outside surface of said first and second end effectors, wherein said straps or

cables when driven by said winch lift a load contacted by said first and second end effectors, and a lower extremity exoskeleton configured to be coupled to a person's lower limbs, wherein said exoskeleton trunk couples to an upper body of said person through an upper body interface device that is coupled to said lower extremity exoskeleton.

16. The system of claim **15**, further comprising a first and a second force sensor in said first and second handles, wherein said first and second force sensors measure a load force which said person is putting on said first and second handles.

17. The system of claim **15**, further comprising a movable counter weight which is rotatable about a counter weight rotation axis by a counterweight actuator so that a mass of said counterweight includes a mass of said winch.

18. The system of claim **17**, further comprising a controller including a microprocessor or microcomputer and a force sensor which measures a force being applied by said load lifting mechanism to said lifting straps or cables, wherein said controller is operable to send a control signal that controls a position of said movable counter weight to a position appropriate to approximately balance a moment created about hip flexion-extension axes by said counter weight with a moment created by the down force on said lifting straps or cables in front of said person.

19. The system of claim **15**, further comprising a load lifting bar mechanism comprising a first and a second lifting bar, which exclusively by pulling said lifting straps or cable, said first and said second lifting bar will move upward and outward when said lifting straps or cable is near an end of its travel.

20. The system of claim **19**, further comprising a lifting bar guide, and cam plate, wherein said lifting bar slides over said lifting bar guide in a telescopic fashion, and

a position of said lifting bar along the lifting bar guide is determined by a cam roller which is mounted on said lifting bar and moves in a slot on said cam plate, said lifting bar guide pivoting on a pivot, and a pulley over which said lifting straps or cables runs, wherein when enough of said lifting straps or cables is retrieved such that said first and second effectors are approaching ends of said lifting bar, said lifting bar starts to move upward and outward as said cam roller moves upward in said slot on said cam plate.

21. The system of claim **20**, wherein said lower extremity exoskeleton comprises leg supports, and said exoskeleton trunk is rotatably connectable to said leg supports at hip flexion-extension joints for hip flexion and extension rotations of leg supports about hip flexion-extension axes.

* * * * *