Supplementary Figure 1: (a) Subject wearing the robotic exoskeleton. (b) Target presentation on a screen using a virtual reality system. (c) An endpoint force \((f_x, f_y)\) vector was mimicked by applying shoulder \((T_s)\) and elbow \((T_e)\) joint torques using the exoskeleton. \(v = (v_x, v_y)\) is the endpoint velocity. \(l_1\) \((l_2)\) and \(\varphi_1\) \((\varphi_2)\) are, respectively, the length and angle (relative to \(x\)-axis) of the upper-arm (forearm).