US010668316B2

(12) **United States Patent**
Mcbride et al.

(10) **Patent No.: US 10,668,316 B2**
(45) **Date of Patent: Jun. 2, 2020**

(54) **METHODS AND APPARATUS FOR BODY WEIGHT SUPPORT SYSTEM**

(71) Applicant: **Bioness Inc.**, Valencia, CA (US)

(72) Inventors: **Keith Mcbride**, Ventura, CA (US); **Arkady Glukhovsky**, Valencia, CA (US); **Augustine Smith**, Santa Clarita, CA (US)

(73) Assignee: **Bioness Inc.**, Valencia, CA (US)

(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 66 days.

(21) Appl. No.: **15/896,731**

(22) Filed: **Feb. 14, 2018**

(65) **Prior Publication Data**

US 2018/0229070 A1 Aug. 16, 2018

Related U.S. Application Data

(60) Provisional application No. 62/458,648, filed on Feb. 14, 2017.

(51) **Int. Cl.**
A63B 21/00 (2006.01)
A63B 24/00 (2006.01)
(Continued)

(52) **U.S. Cl.**
CPC ***A63B 21/4001*** (2015.10); ***A63B 21/00181*** (2013.01); ***A63B 21/068*** (2013.01);
(Continued)

(58) **Field of Classification Search**
CPC A63B 21/4001; A63B 69/0002; A63B 21/00181; A63B 24/0087; A63B 23/0464;
(Continued)

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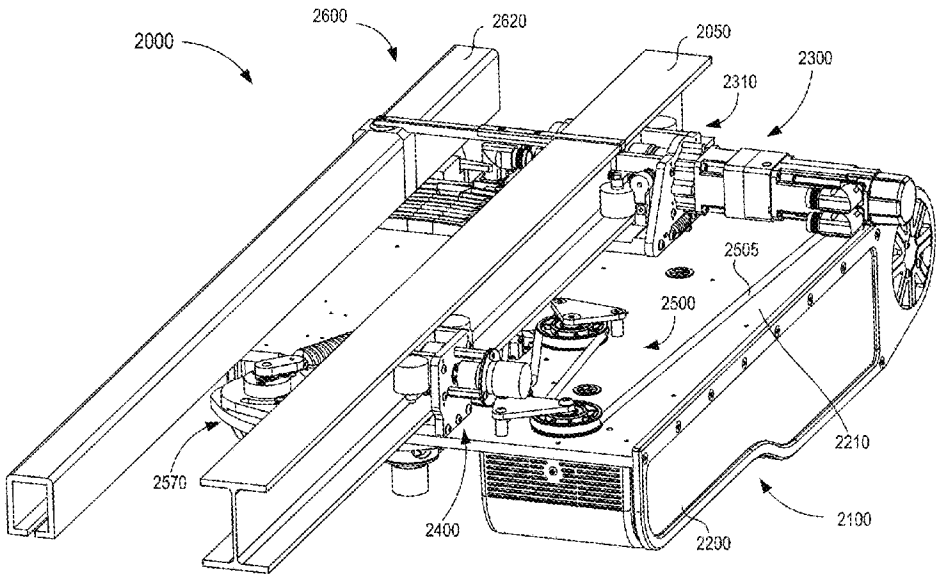
Primary Examiner — Garrett K Atkinson
(74) *Attorney, Agent, or Firm* — Cooley LLP

(57) **ABSTRACT**

A body weight support system includes a tether configured to be coupled to an attachment device worn by a user to couple the user to the body weight support system. A method of providing gait training includes defining a reference length of the tether when the attachment device is in an initial position and defining a threshold length of the tether. A first amount of body weight support is provided during the gait training as the user moves relative to a surface and the length of the tether is less than the threshold length. A second amount of body weight support is provided during the gait training as the user moves relative to the surface and the length of the tether is greater than the threshold length. The method further includes displaying data associated with the gait training on a display of an electronic device.

19 Claims, 69 Drawing Sheets



IPR2023-00428 (Aretech LLC v. Bioness Inc.)
Aretech LLC - Exhibit 1001, Page 00001

(51) **Int. Cl.**

A63B 21/068	(2006.01)
A63B 69/00	(2006.01)
A63B 23/04	(2006.01)
A63B 22/00	(2006.01)
A63B 71/00	(2006.01)
A63B 22/02	(2006.01)
A63B 71/06	(2006.01)

(52) **U.S. Cl.**

CPC ***A63B 23/0464*** (2013.01); ***A63B 24/0087*** (2013.01); ***A63B 69/0002*** (2013.01); ***A63B 69/0064*** (2013.01); *A63B 21/4007* (2015.10); *A63B 22/0235* (2013.01); *A63B 23/0458* (2013.01); *A63B 71/0622* (2013.01); *A63B 2022/0092* (2013.01); *A63B 2022/0094* (2013.01); *A63B 2024/0093* (2013.01); *A63B 2071/0018* (2013.01); *A63B 2208/0204* (2013.01); *A63B 2220/10* (2013.01); *A63B 2220/30* (2013.01); *A63B 2220/40* (2013.01); *A63B 2220/51* (2013.01); *A63B 2220/54* (2013.01); *A63B 2220/805* (2013.01); *A63B 2225/20* (2013.01); *A63B 2225/50* (2013.01)

(58) **Field of Classification Search**

CPC A63B 21/068; A63B 69/0064; A63B 21/4007; A63B 2225/50; A63B 2225/20; A63B 2220/805; A63B 2220/54; A63B 2220/51; A63B 2220/40; A63B 2220/30; A63B 2220/10; A63B 2071/0018; A63B 2024/0093; A63B 23/0458; A63B 22/0235; A63B 71/0622; A63B 2022/0092; A63B 2208/0204; A63B 2022/0094

See application file for complete search history.

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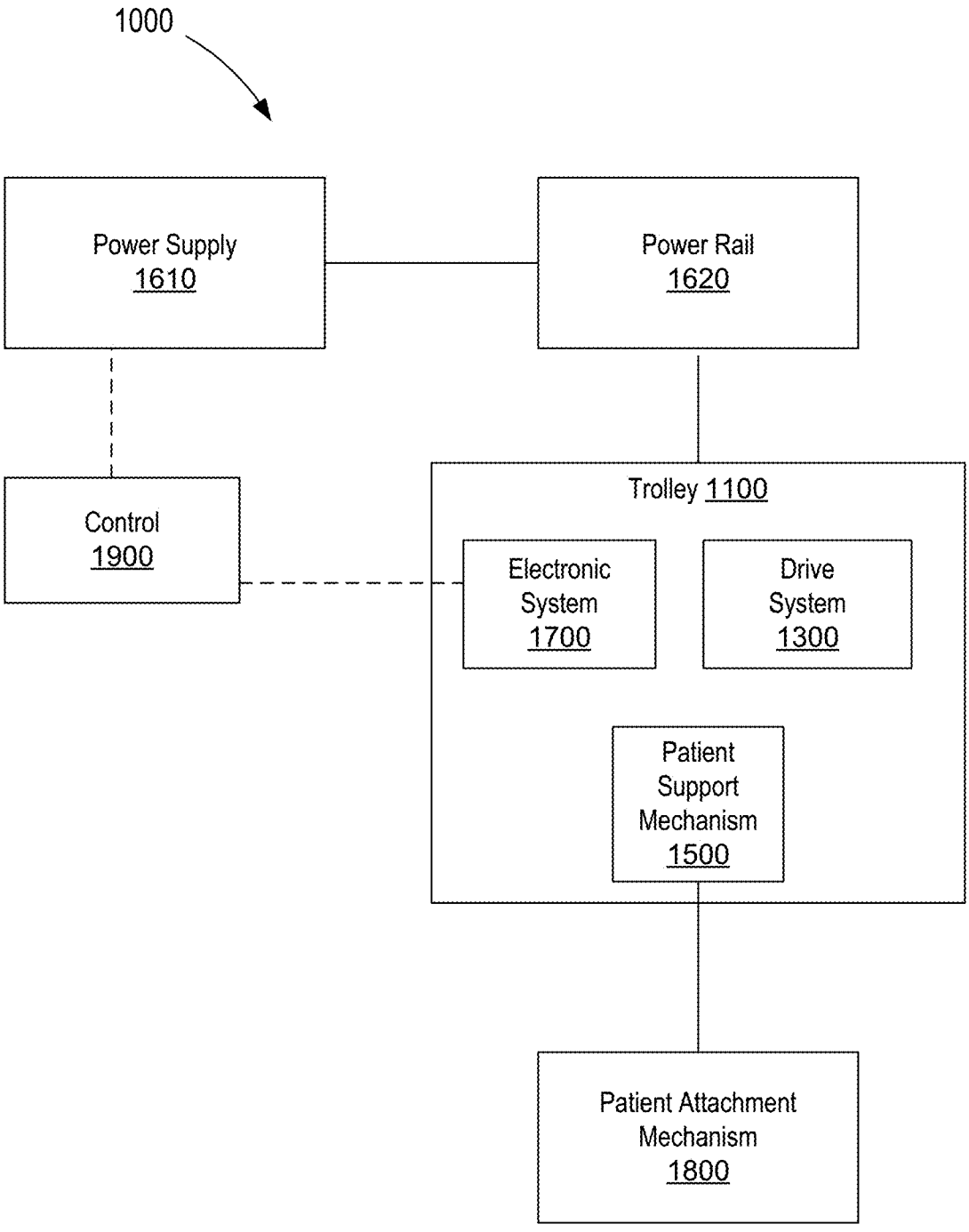
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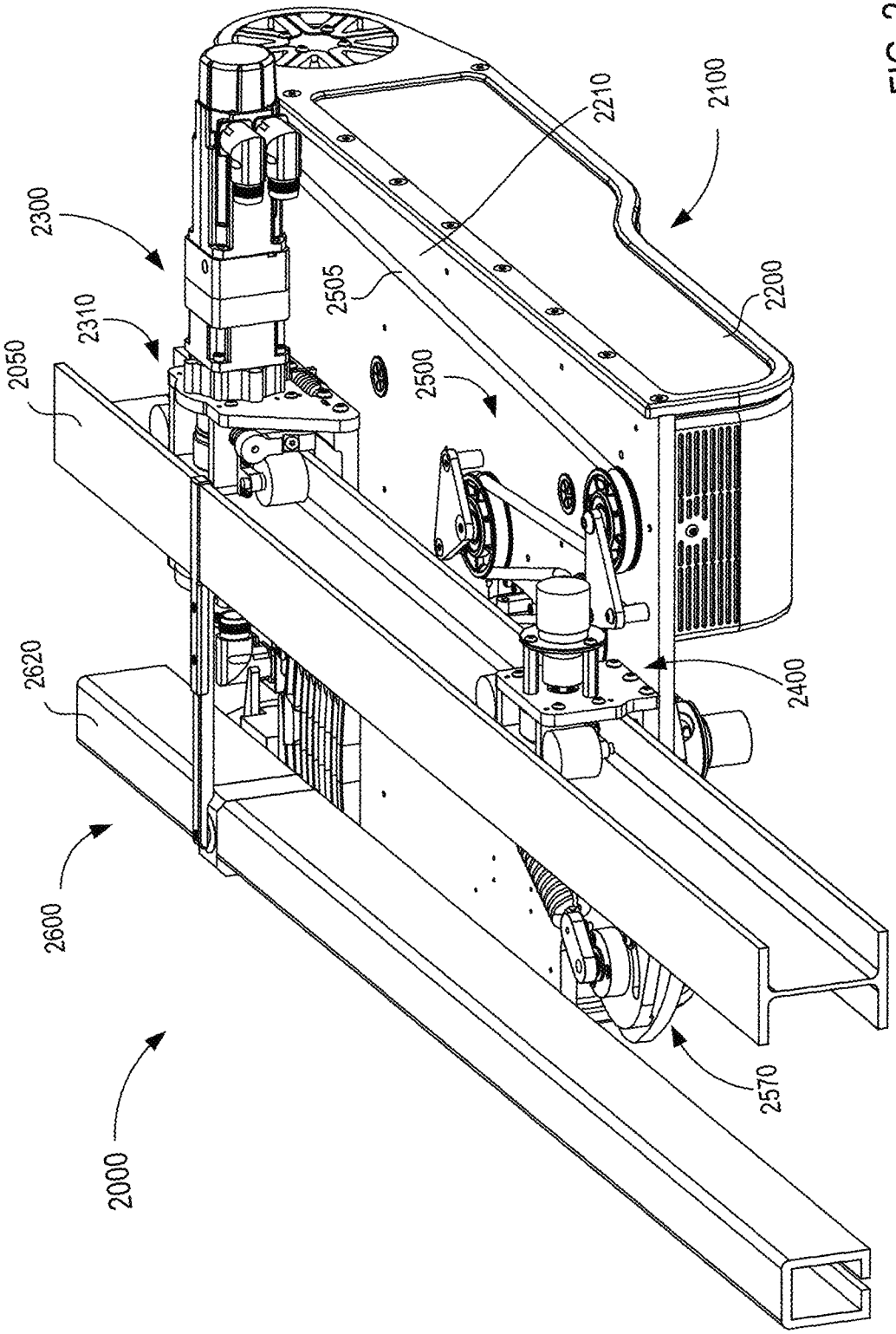
FIG. 1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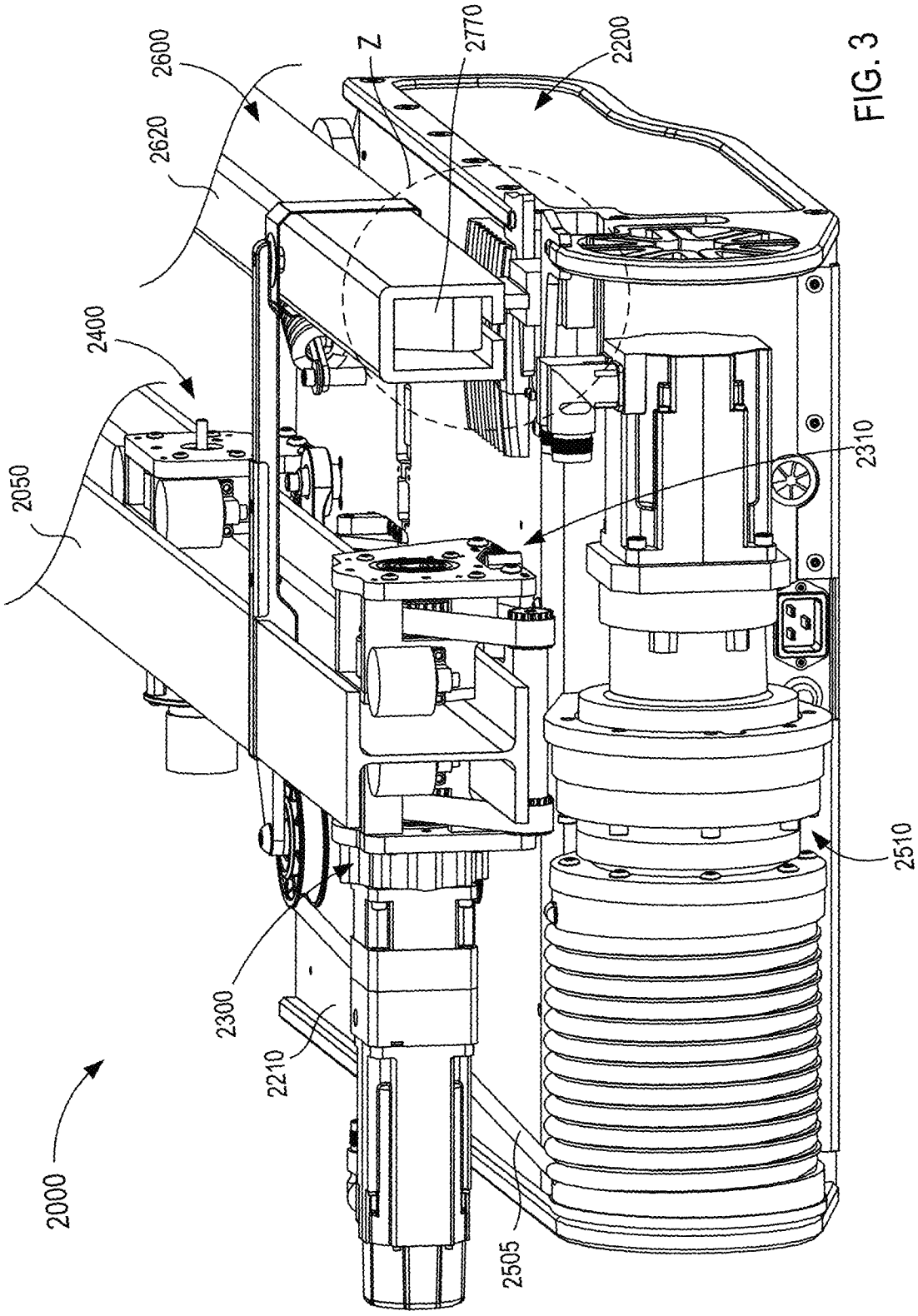

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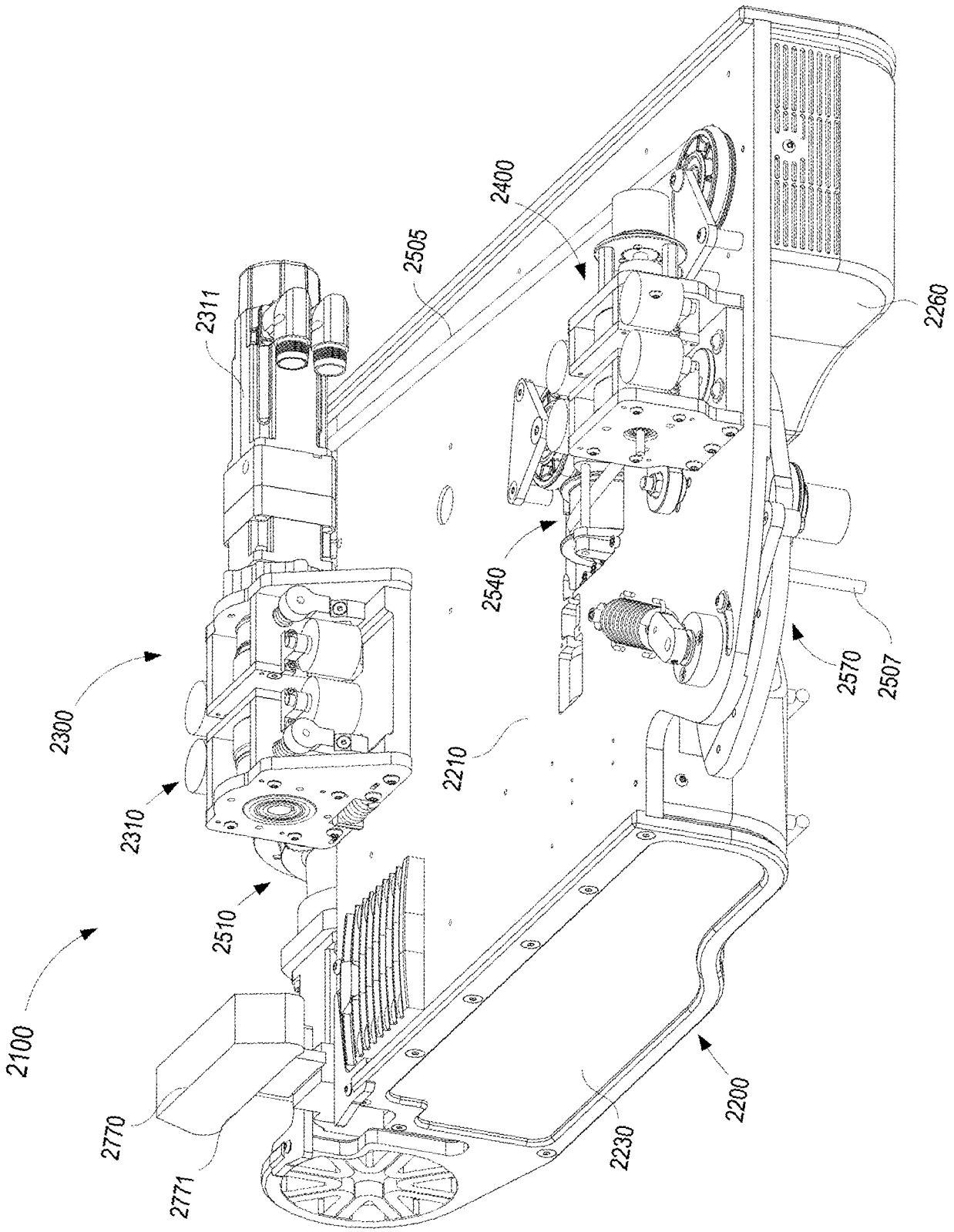
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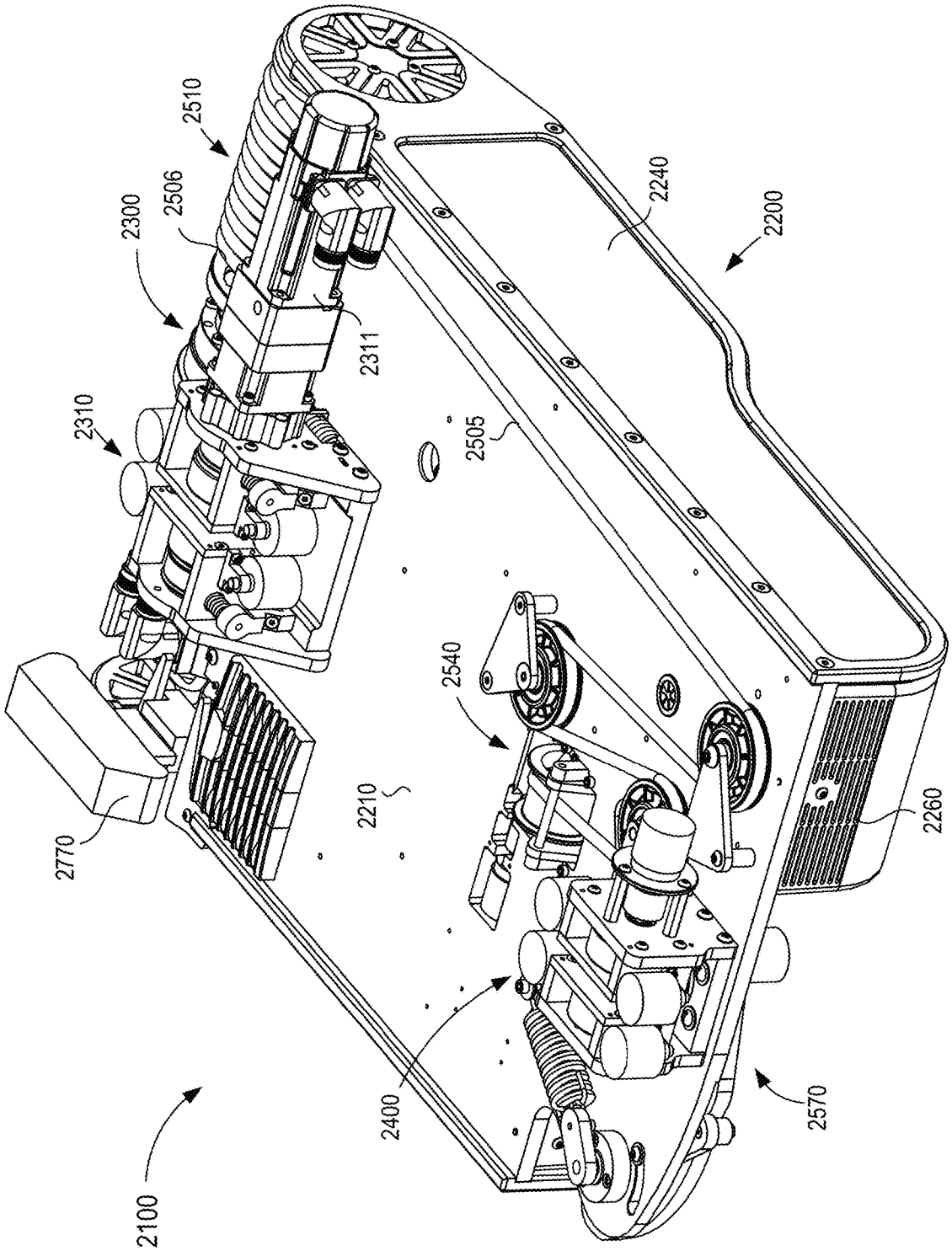
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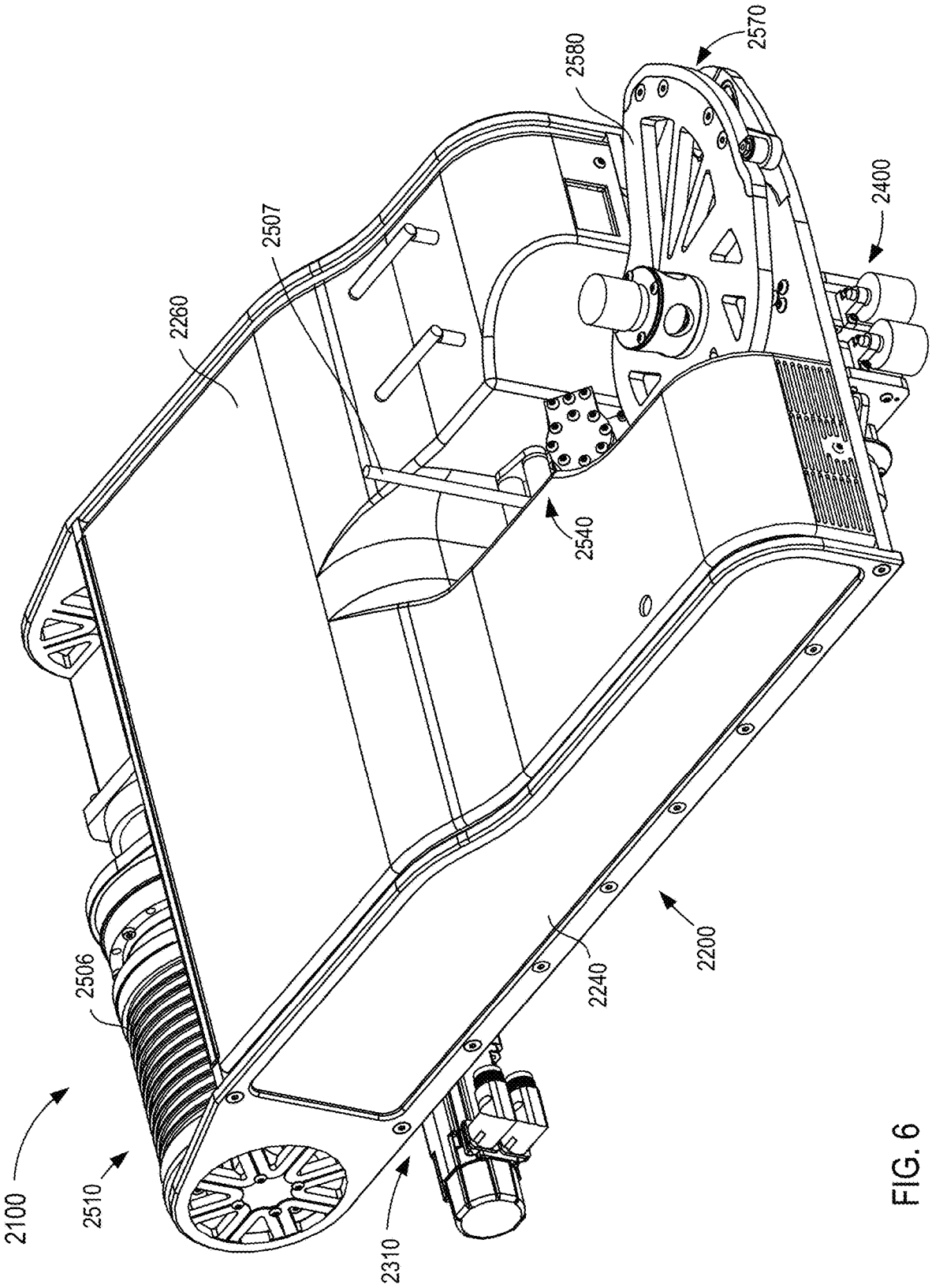

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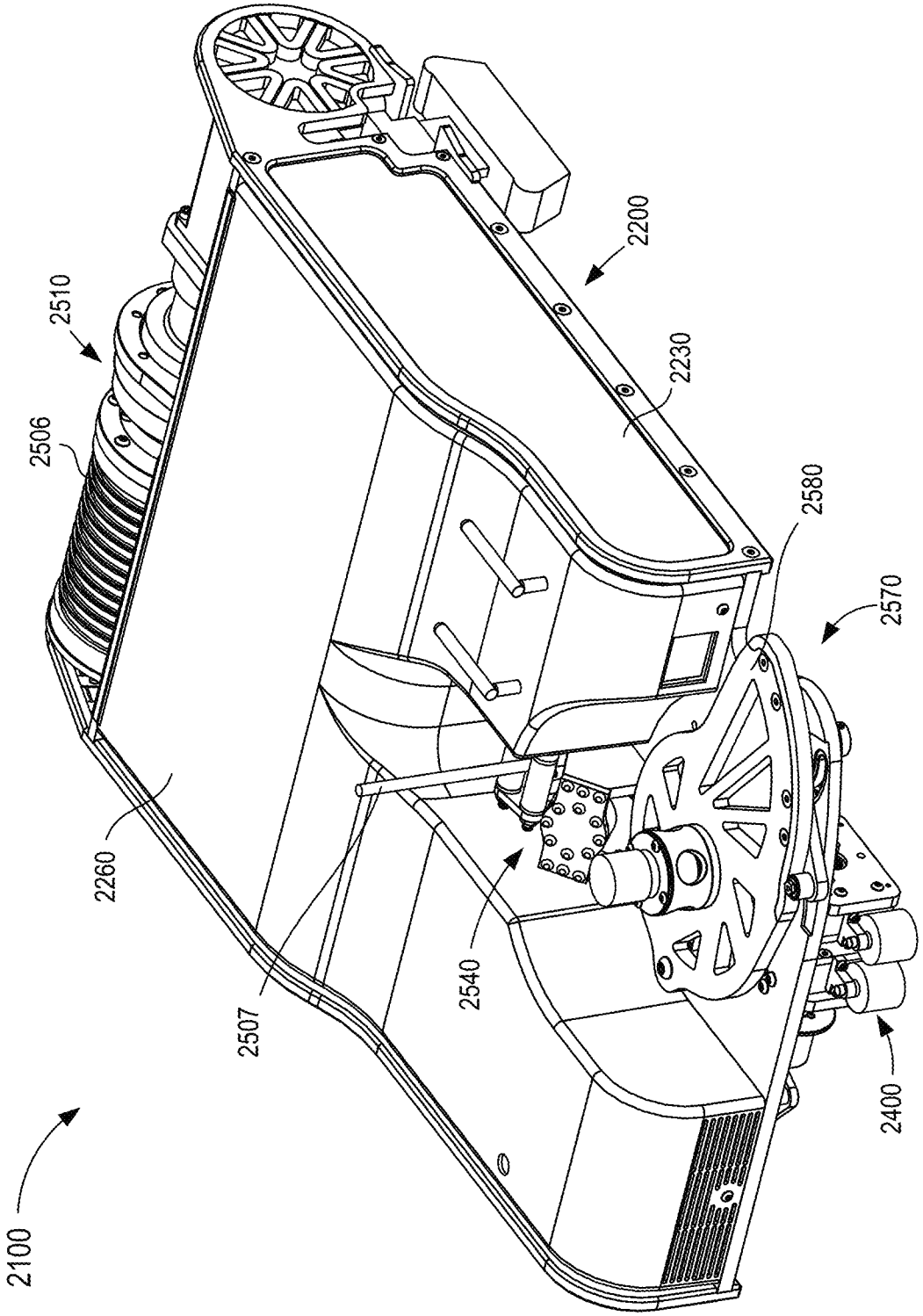

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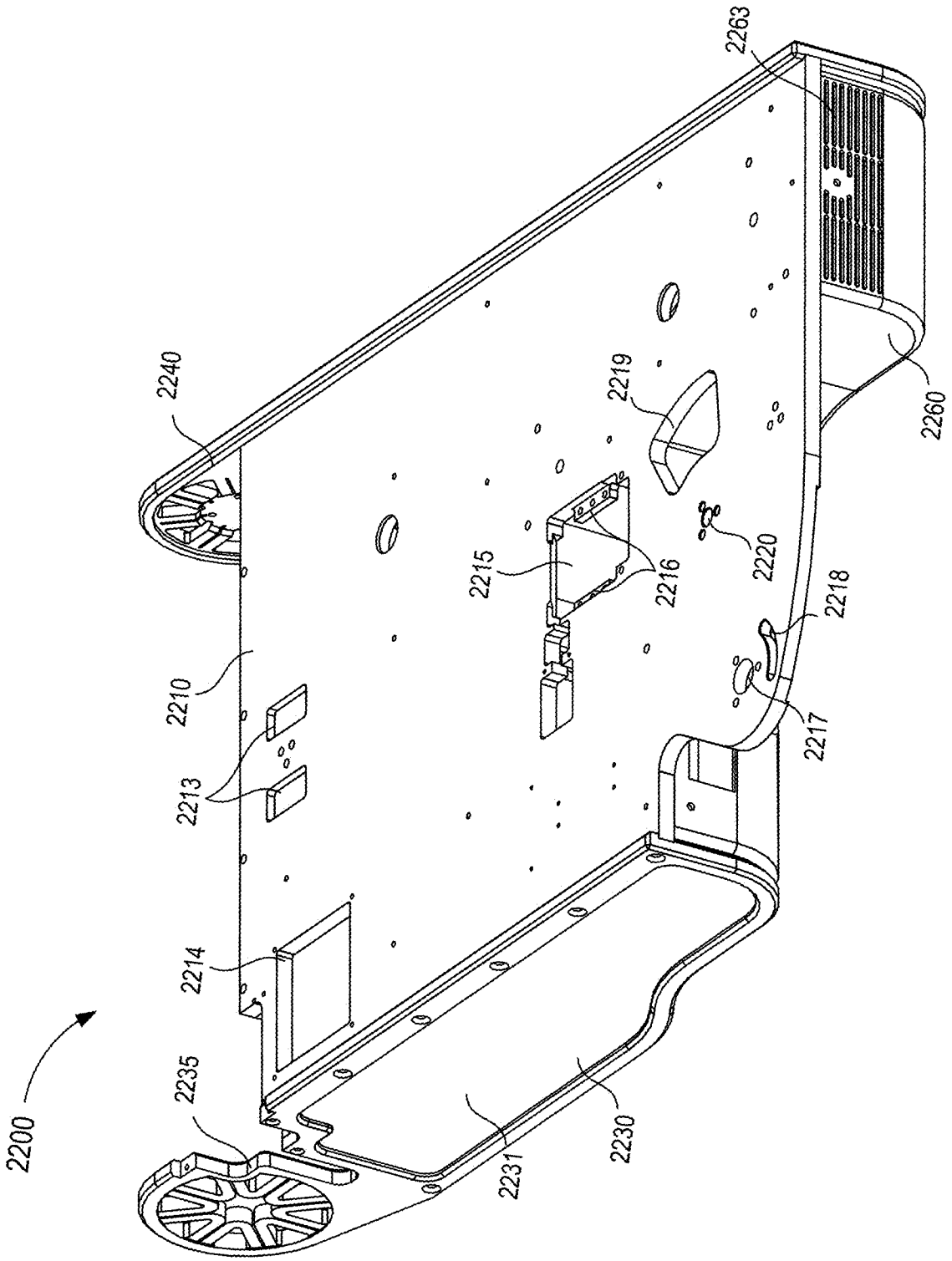
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FIG. 8

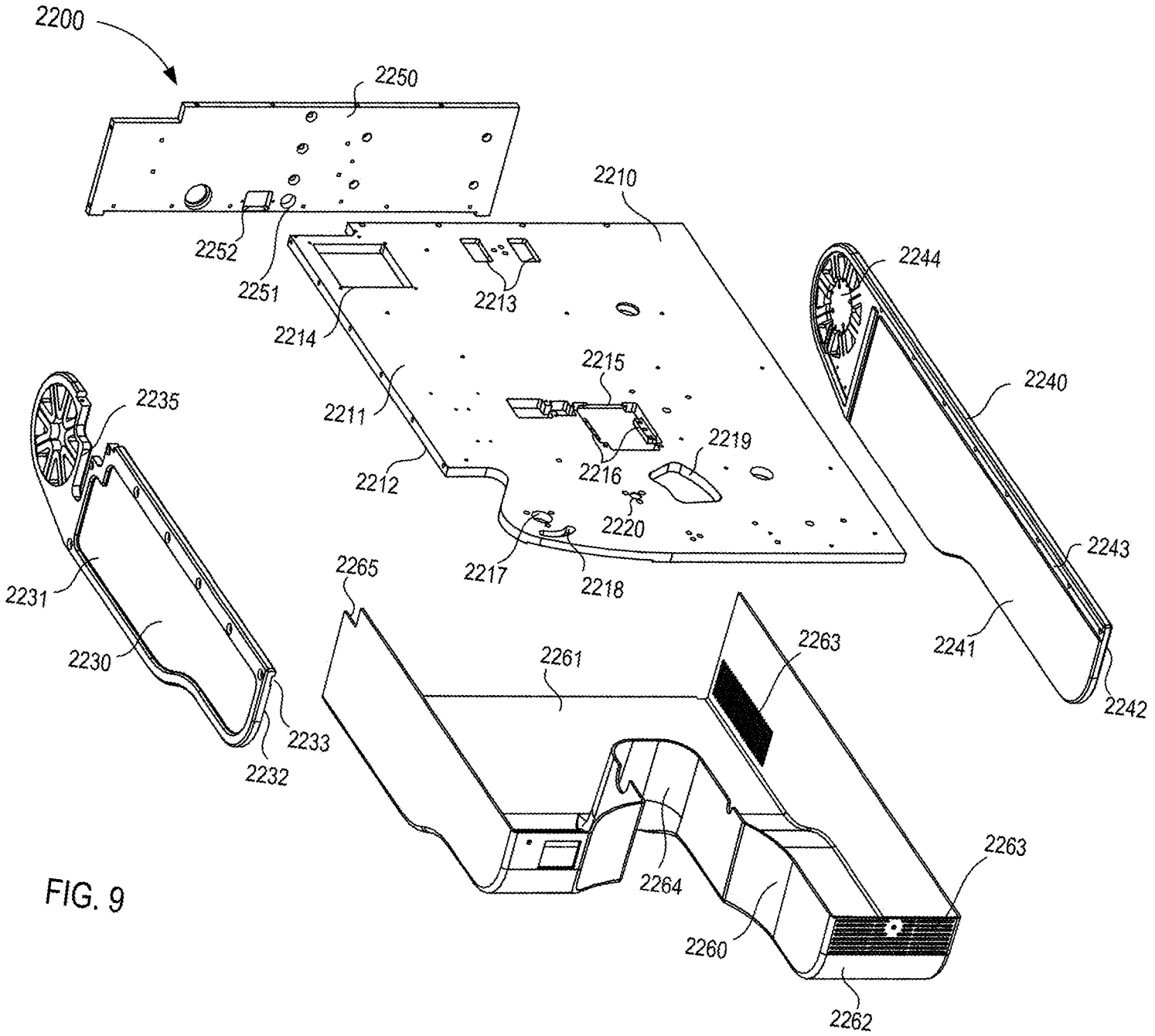
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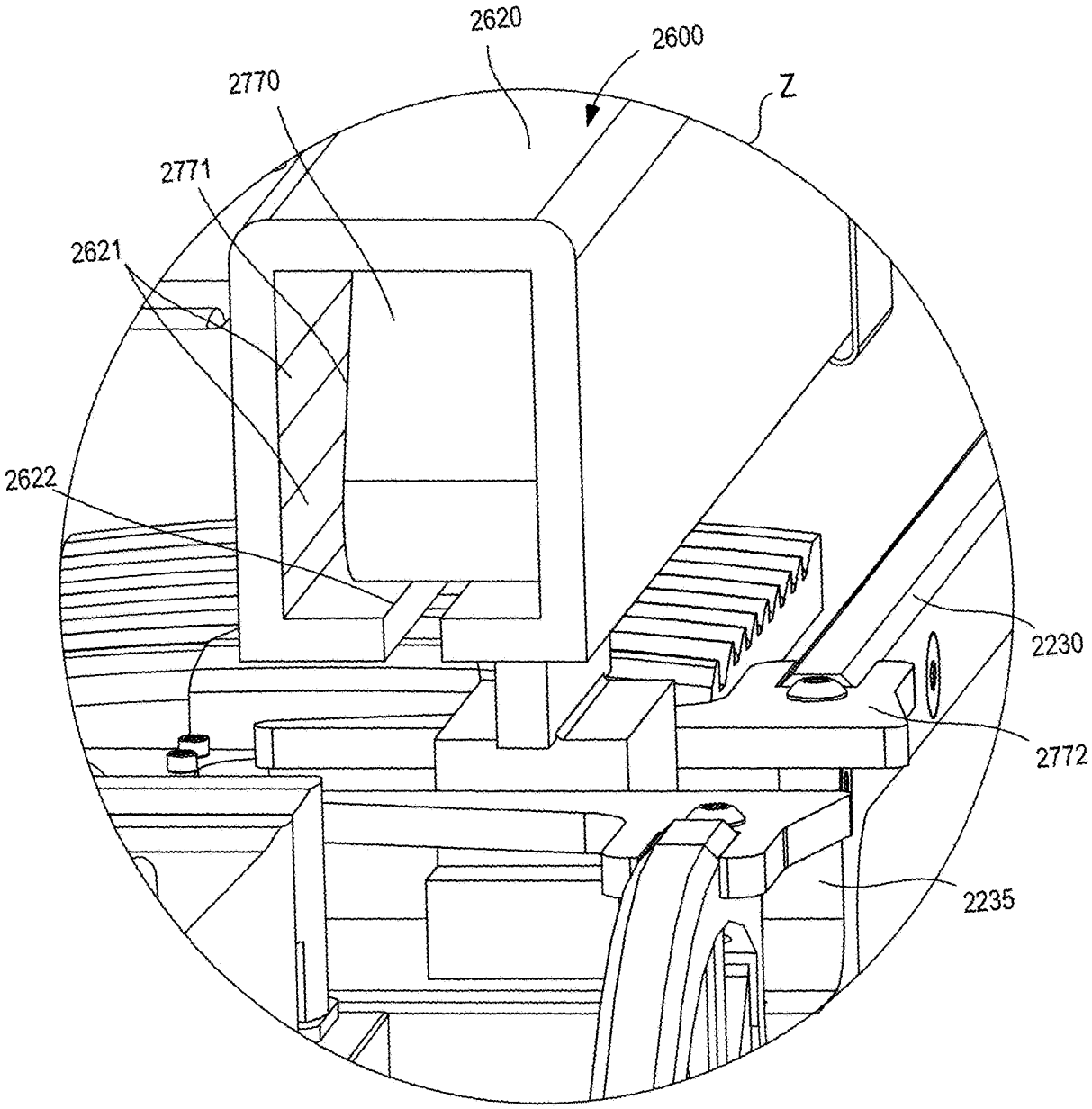
FIG. 9



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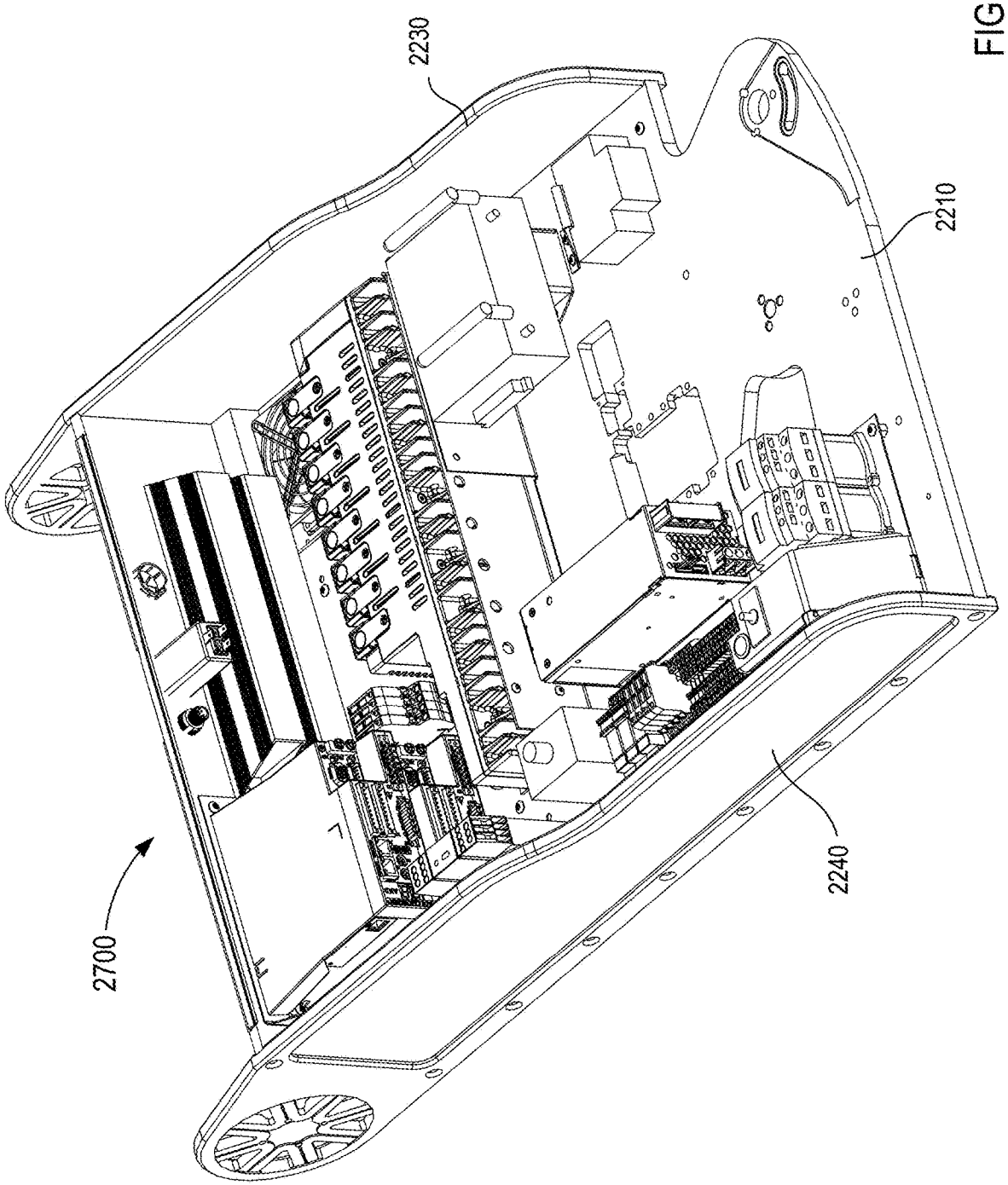

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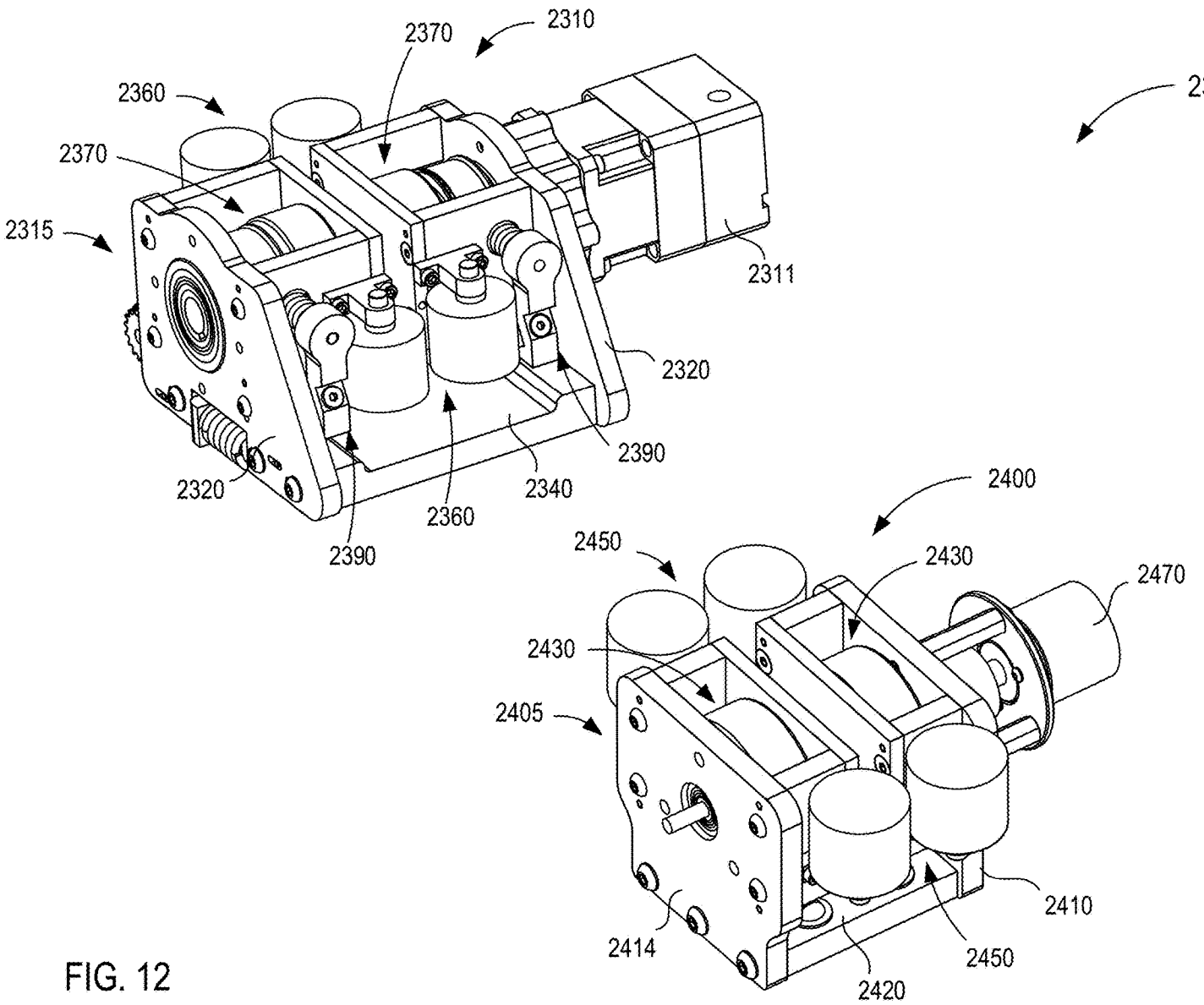
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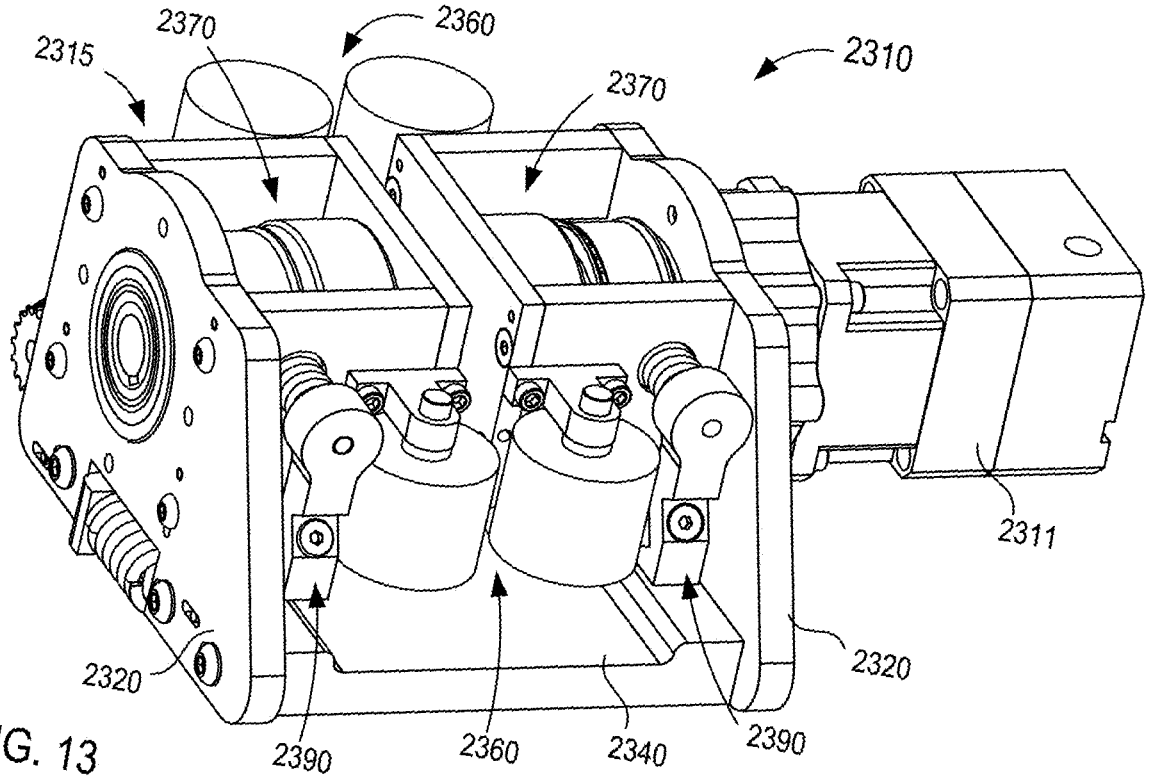
FIG. 12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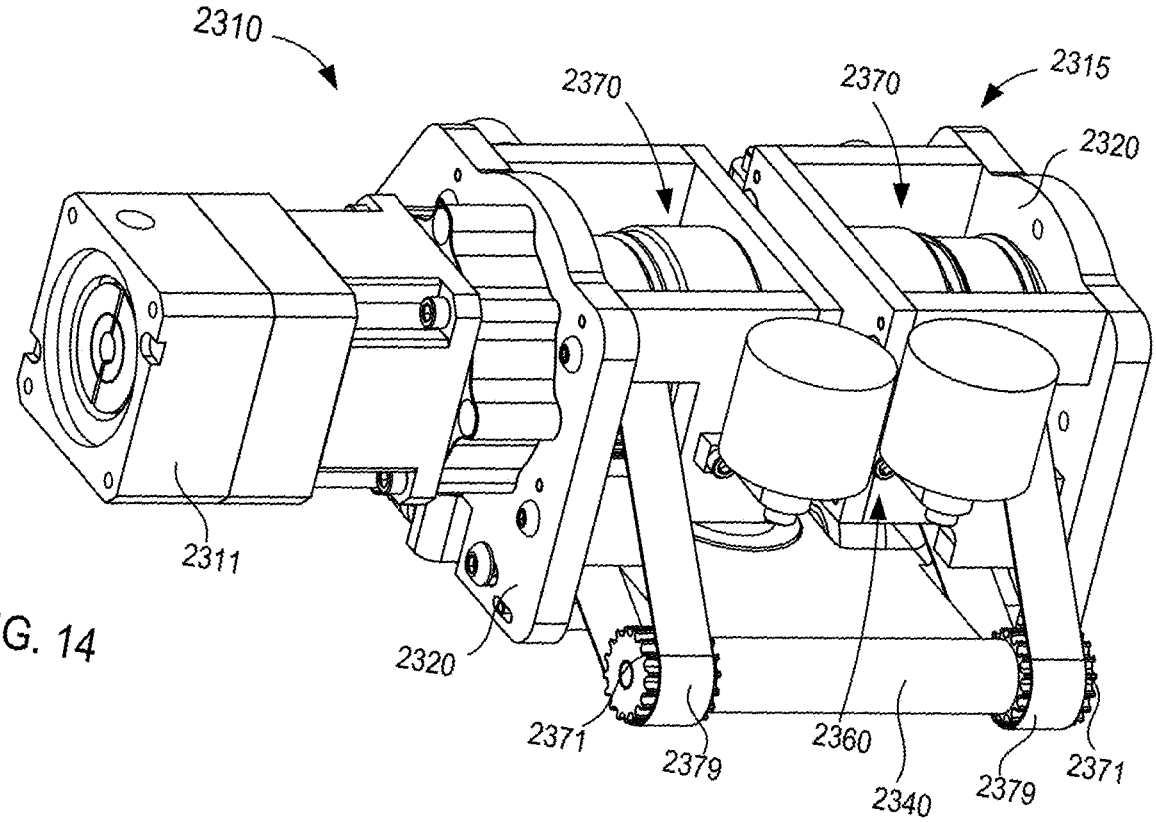
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FIG. 14

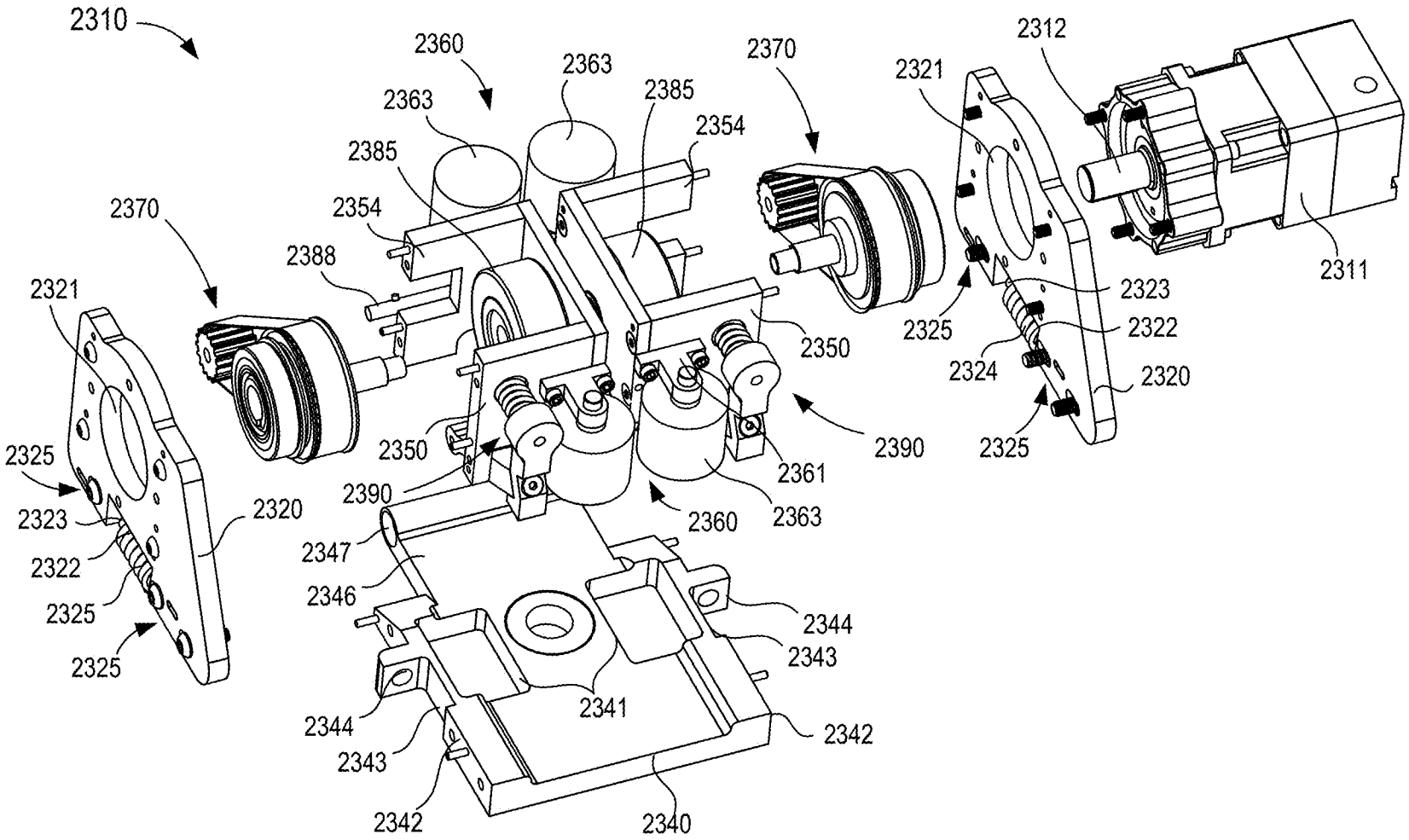
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FIG. 15

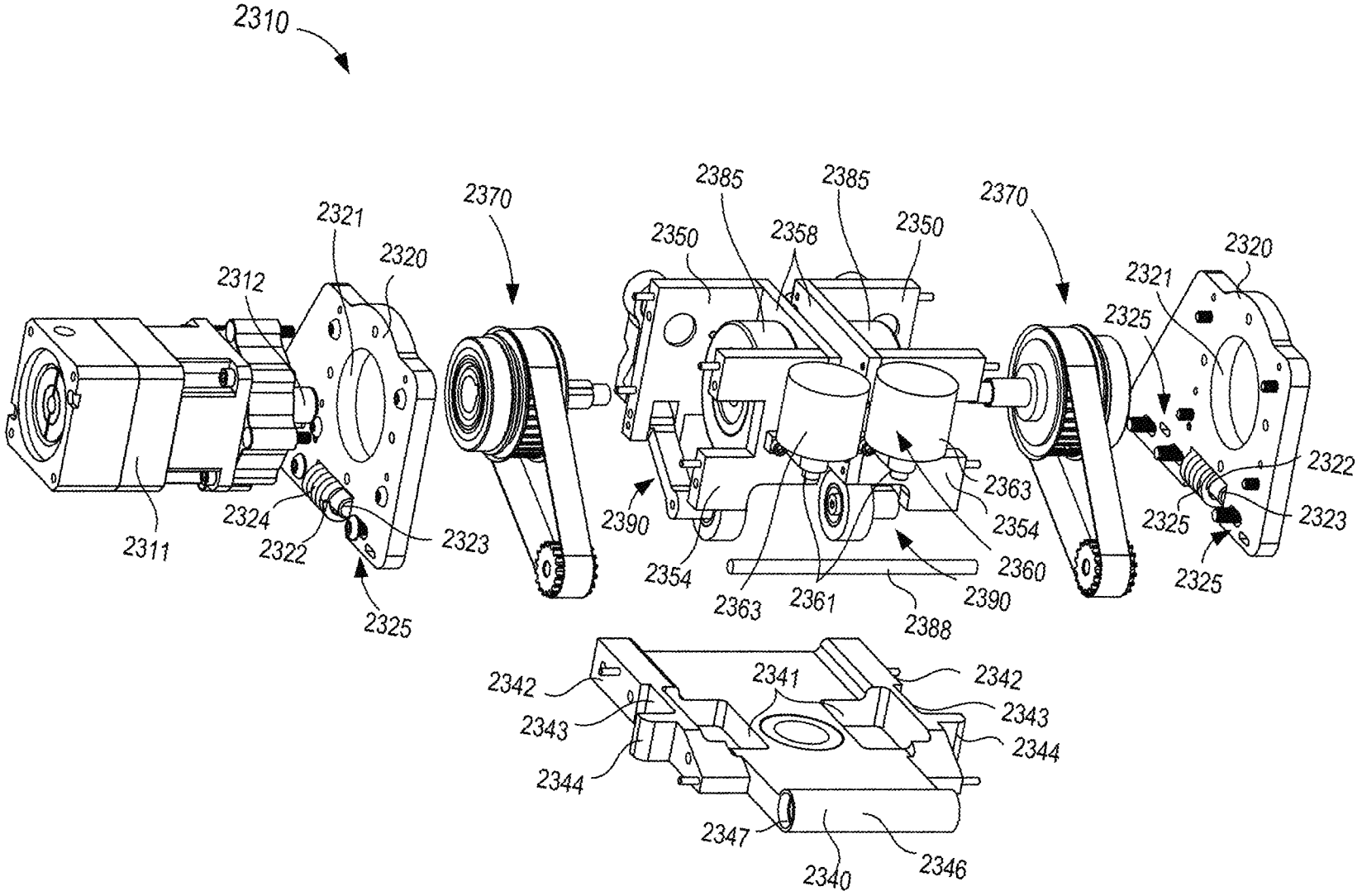
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FIG. 16

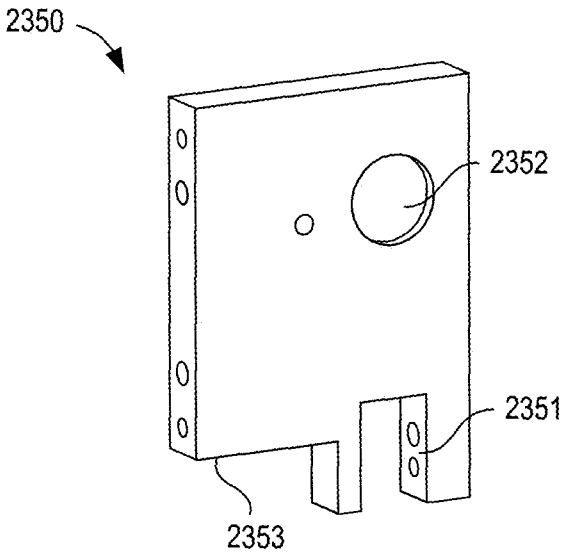

FIG. 17

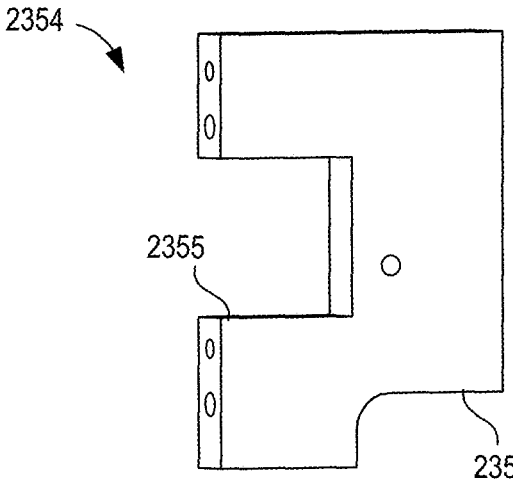

FIG. 18

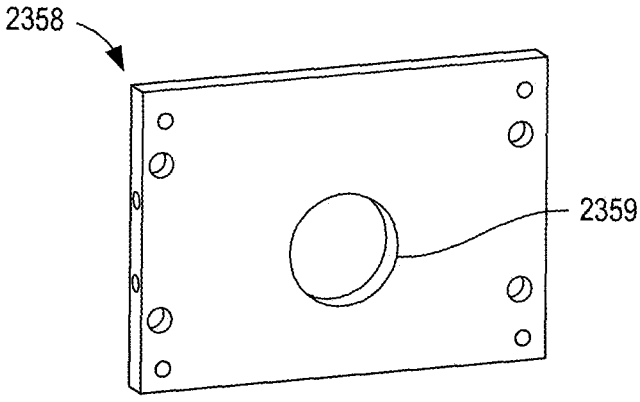

FIG. 19

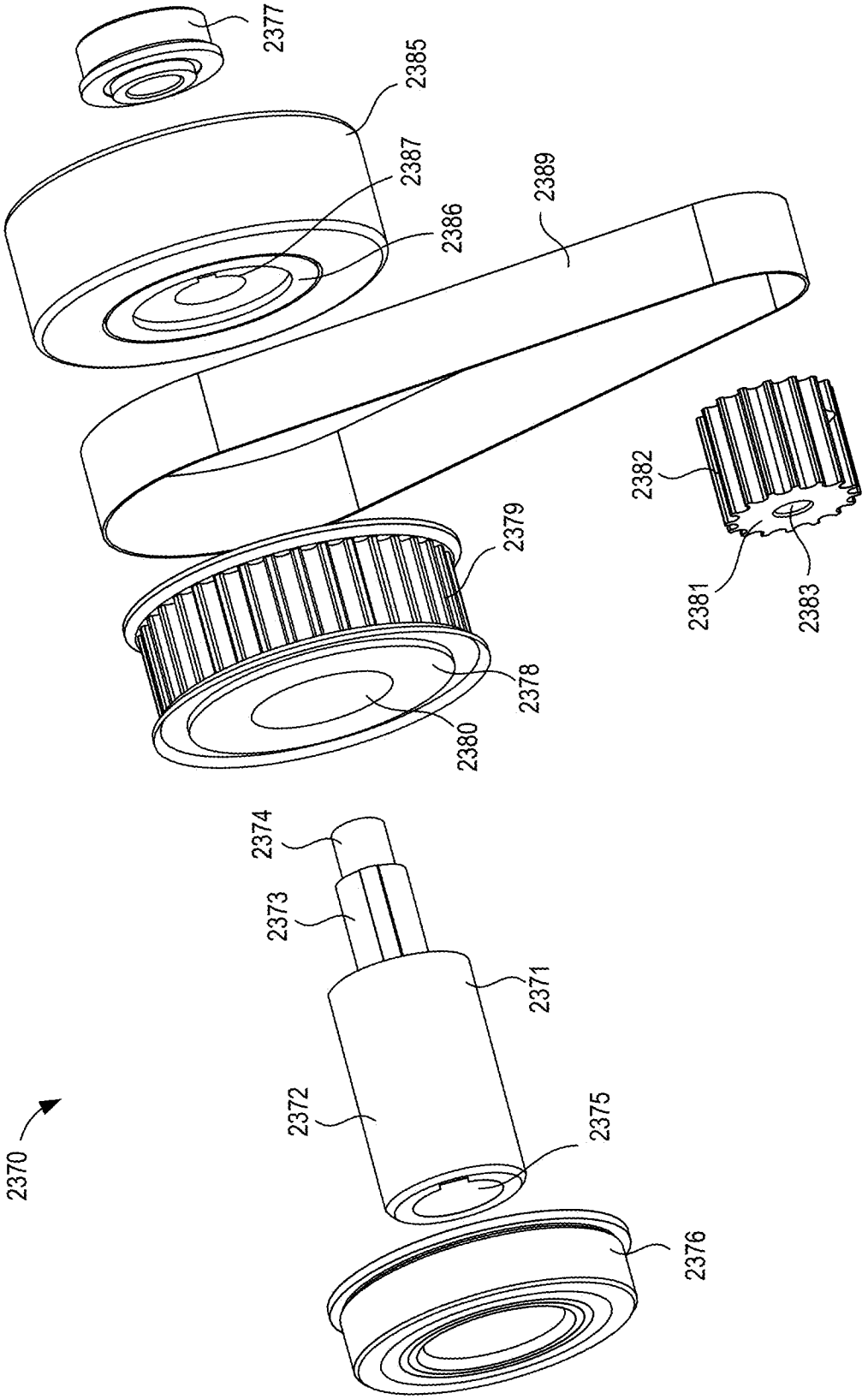
2377
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FIG. 20

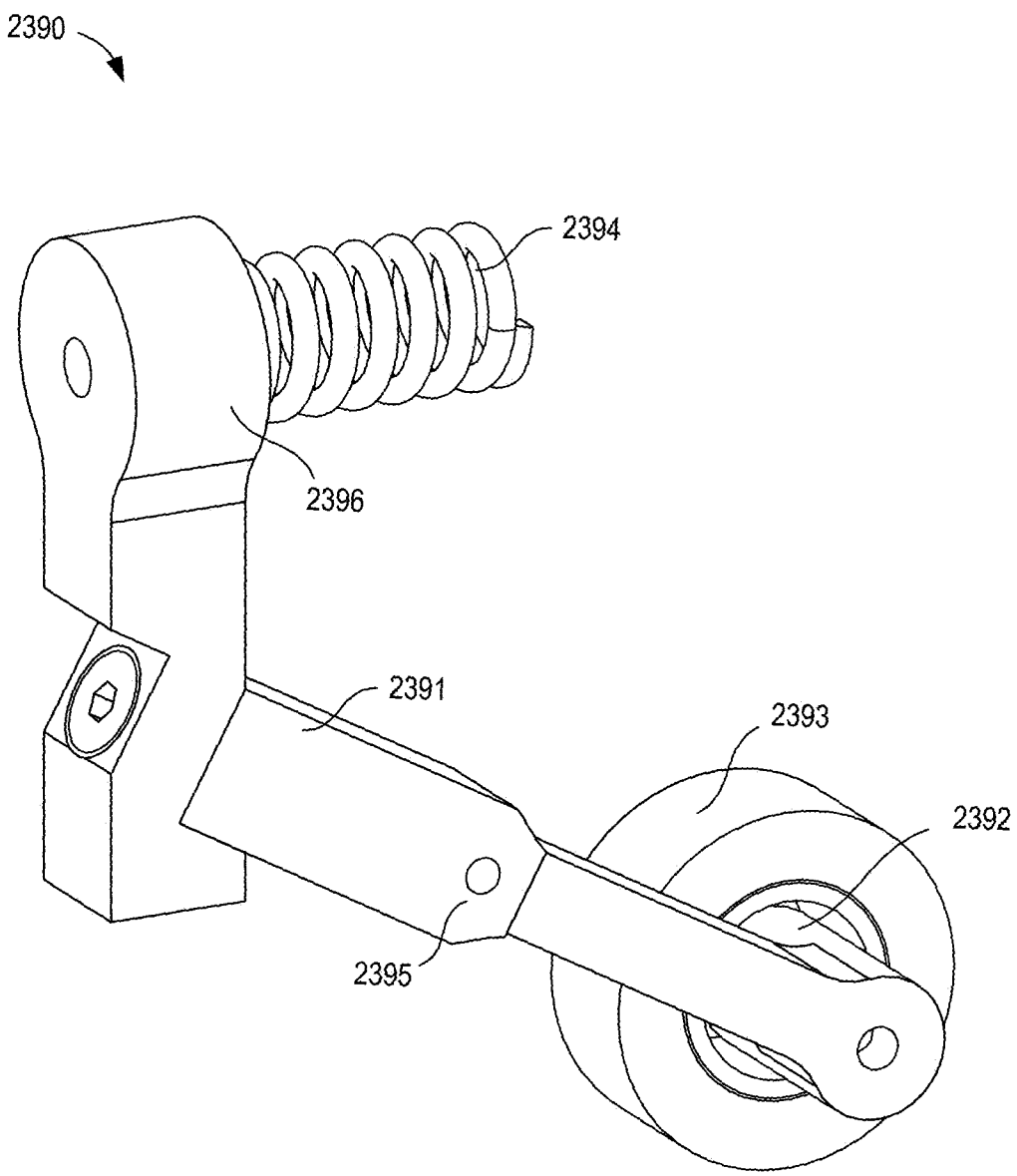
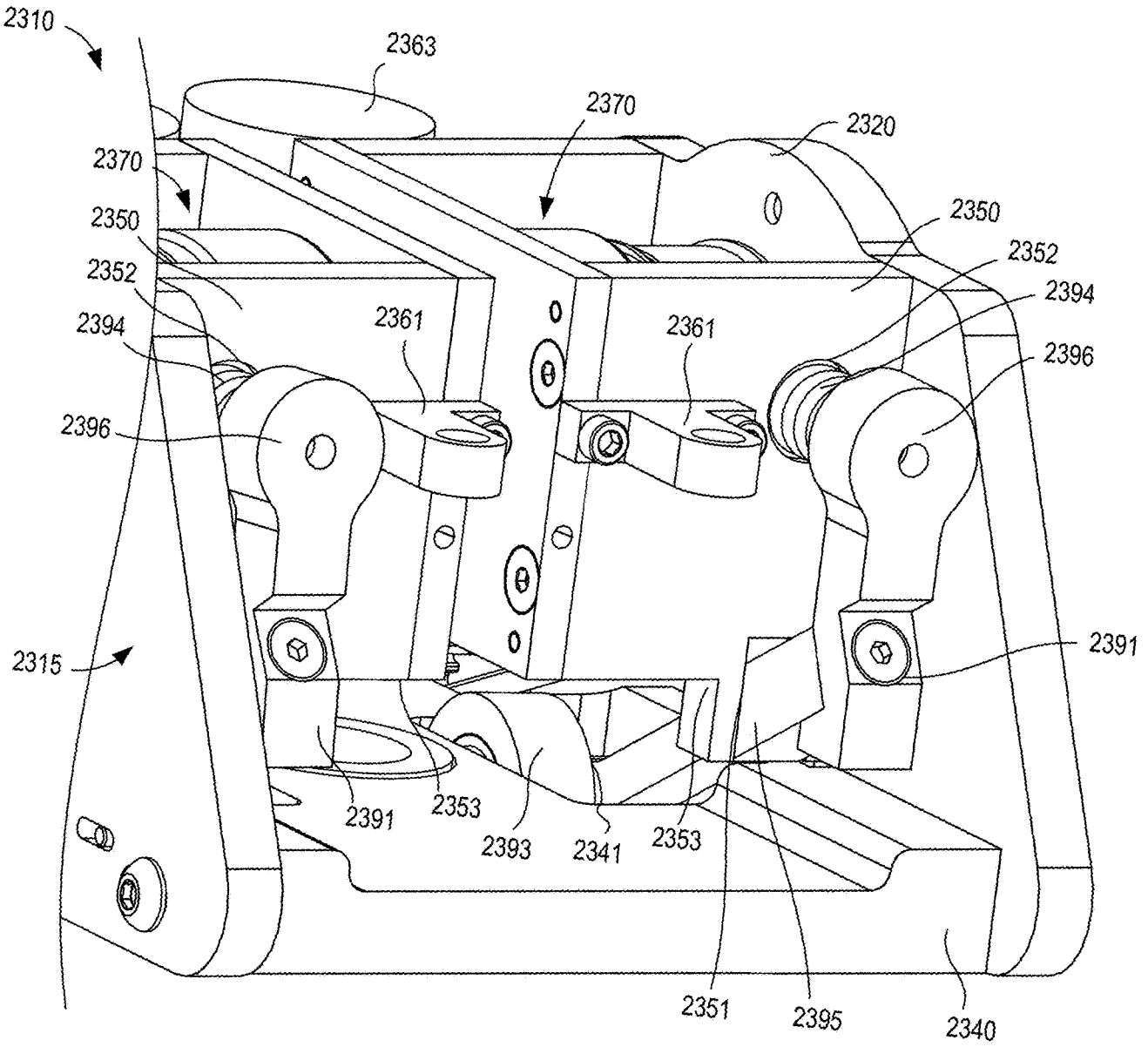


FIG. 21


2310
2363
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2393
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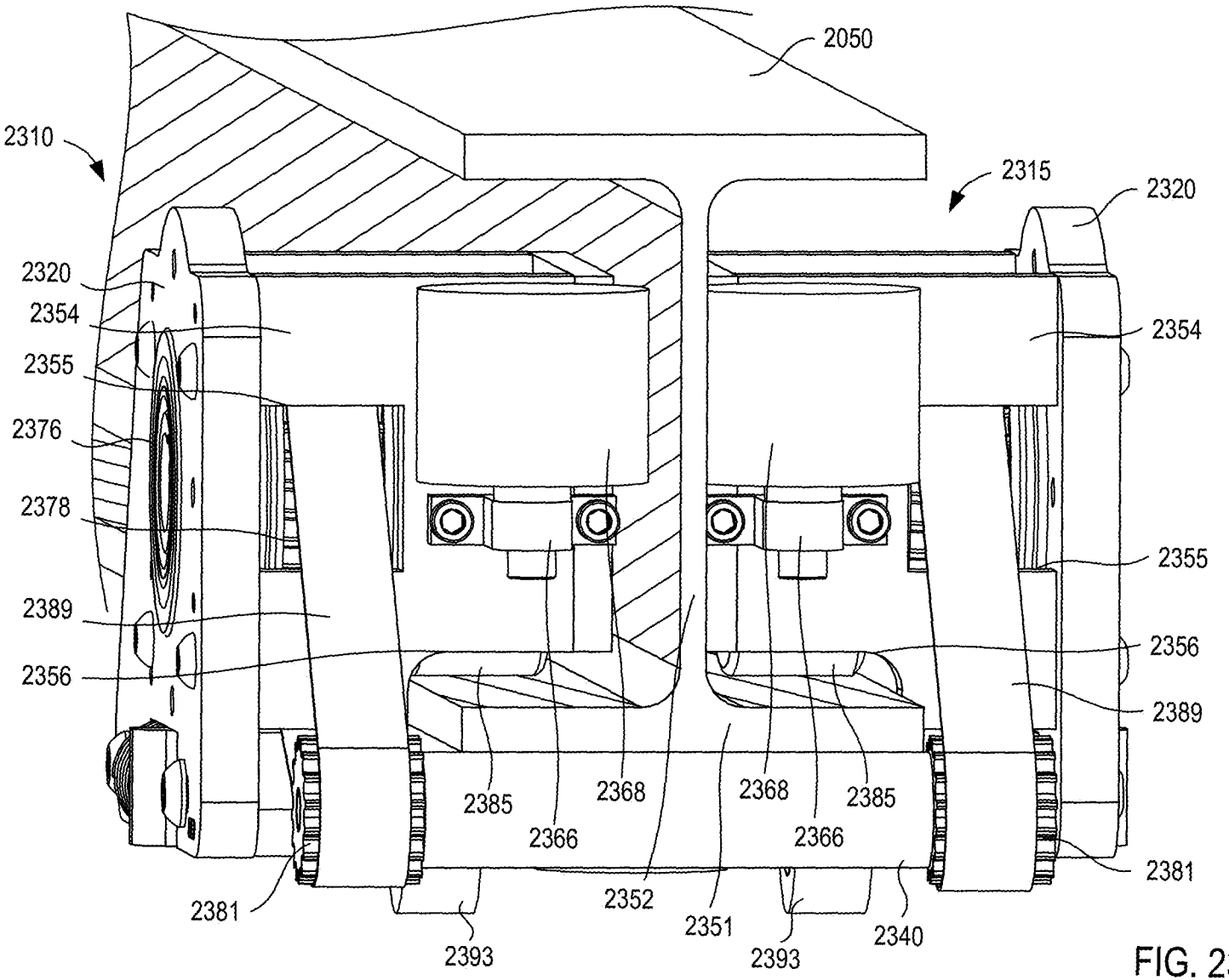
2340

FIG. 22


2050
2310
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2376
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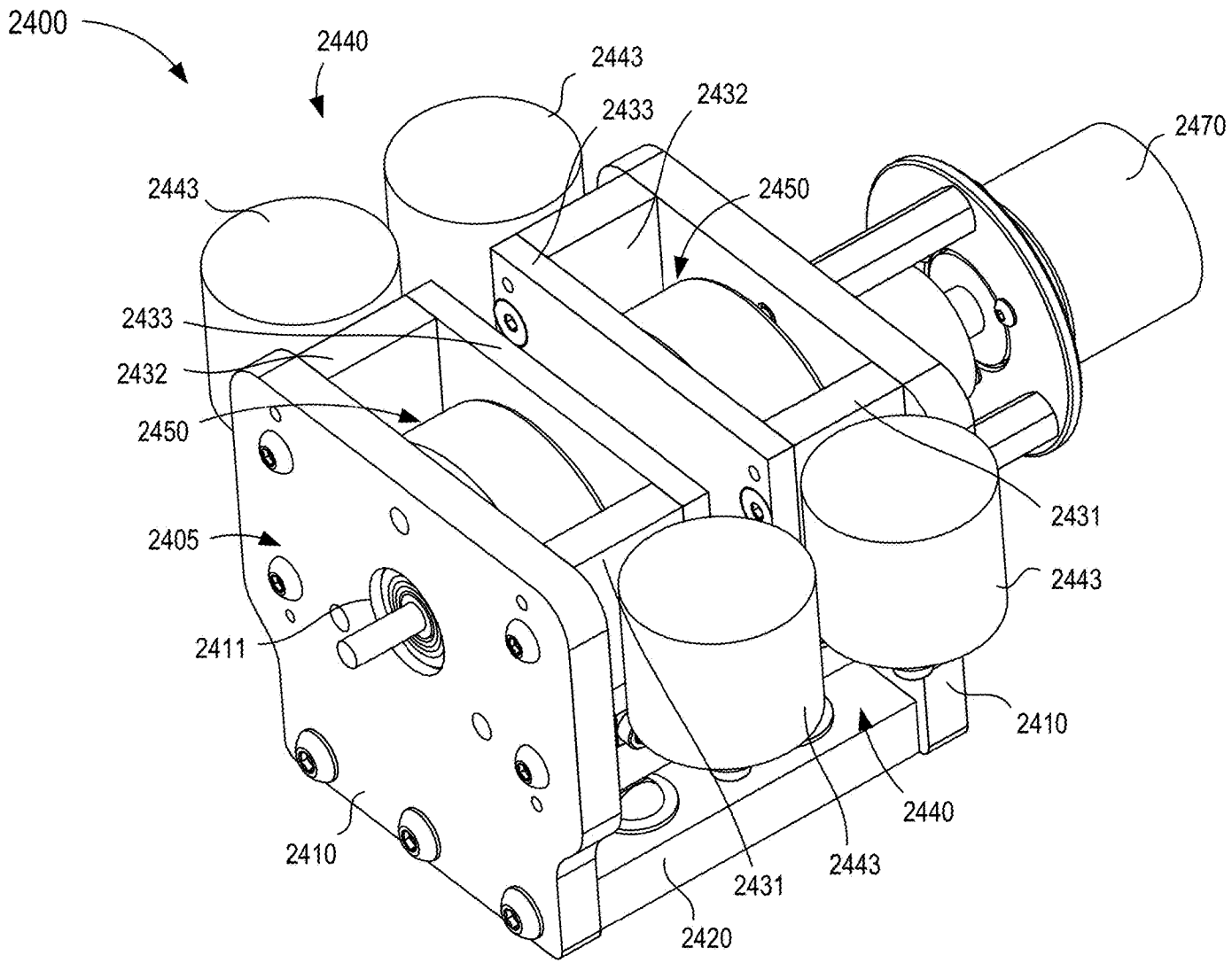
FIG. 23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2440
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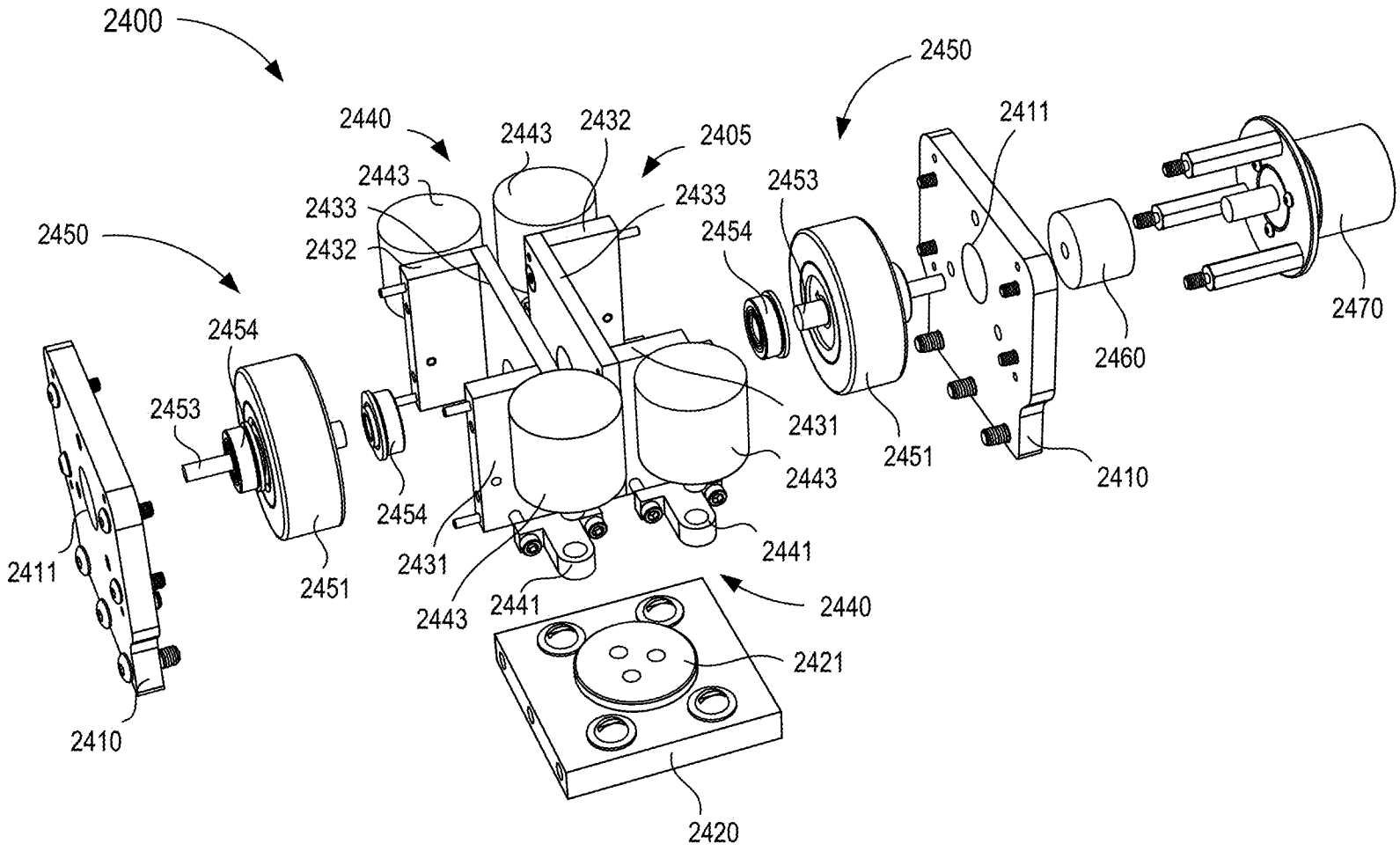
FIG. 24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2454
2470
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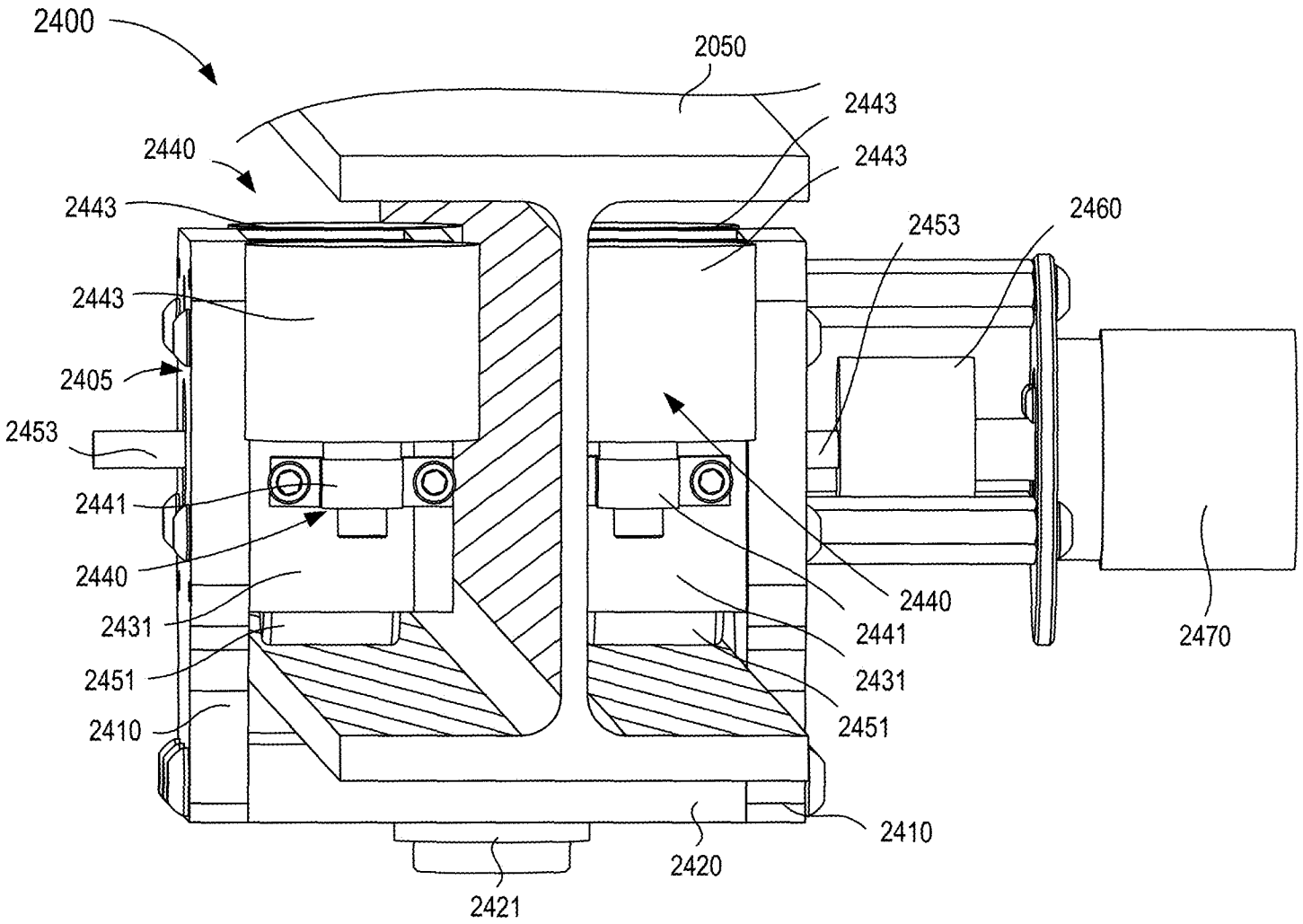
FIG. 25


2400
2050
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2443
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2460
2453
2443
2405
2453
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2440
2441
2431
2451
2410
2420
2421
2470

FIG. 26

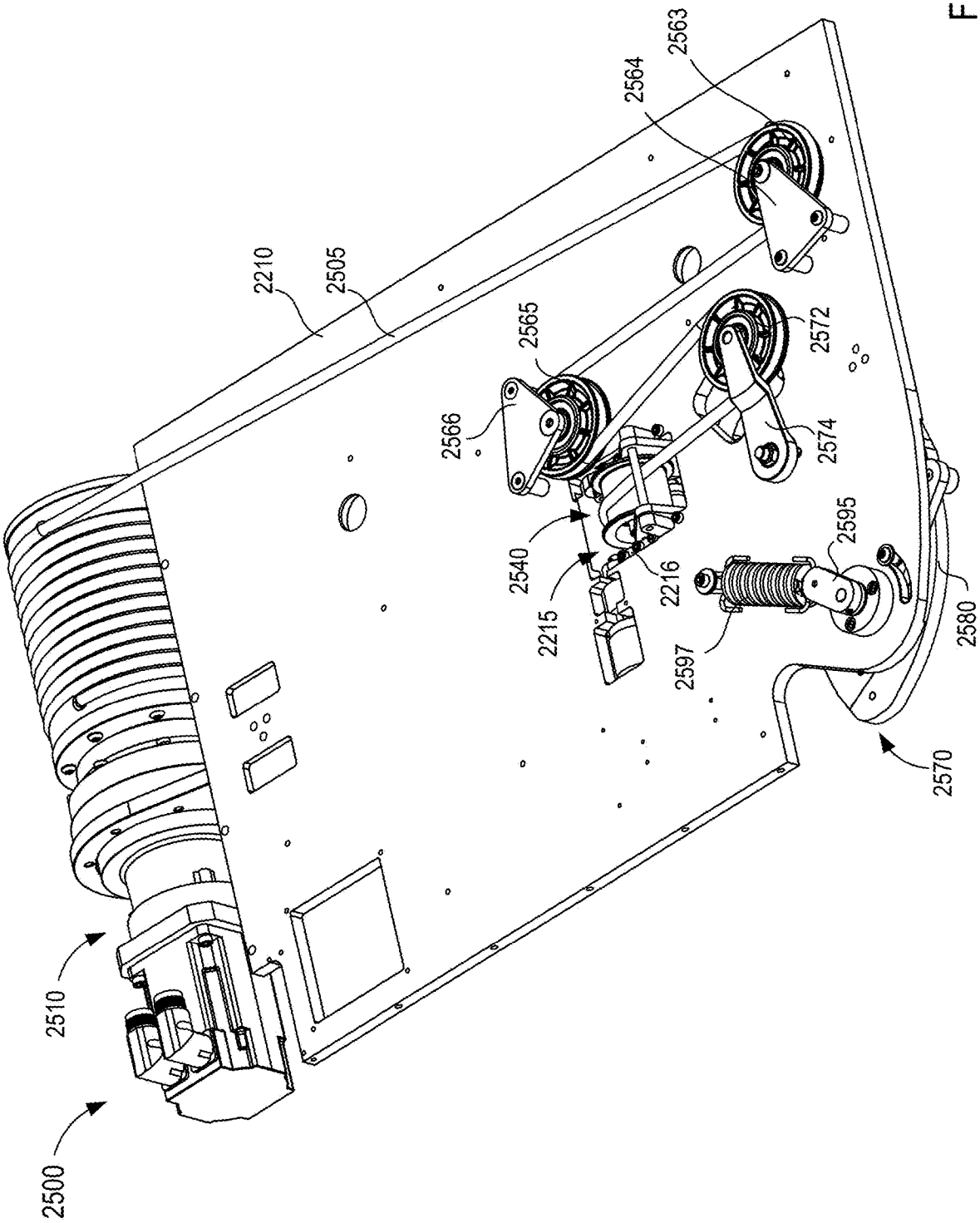
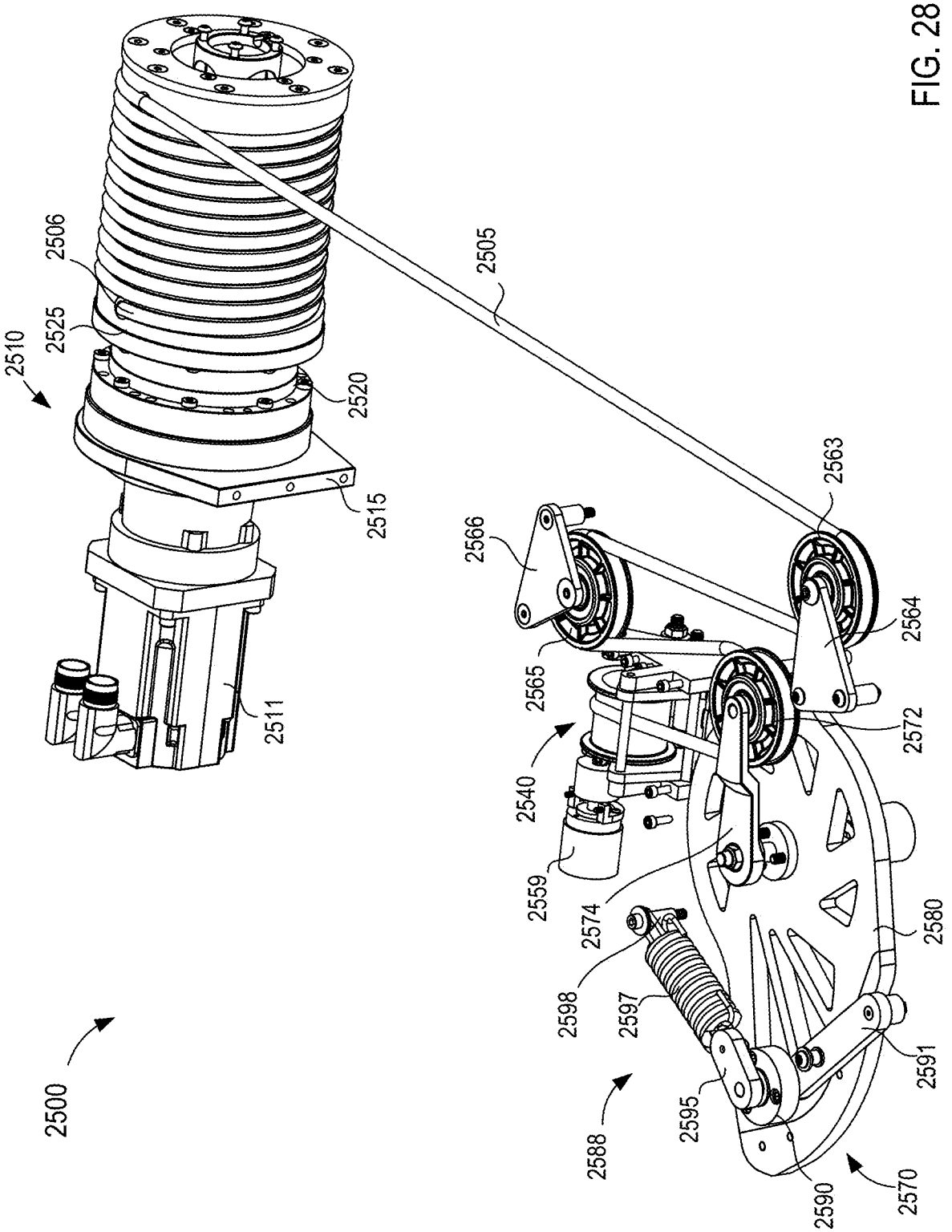

2500
2510
2210
2505
2563
2564
2565
2566
2572
2574
2540
2215
2216
2595
2597
2580
2570

FIG. 27


2500
2505
2506
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2540
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2572
2574
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2588
2590
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2595
2597
2598

FIG. 28

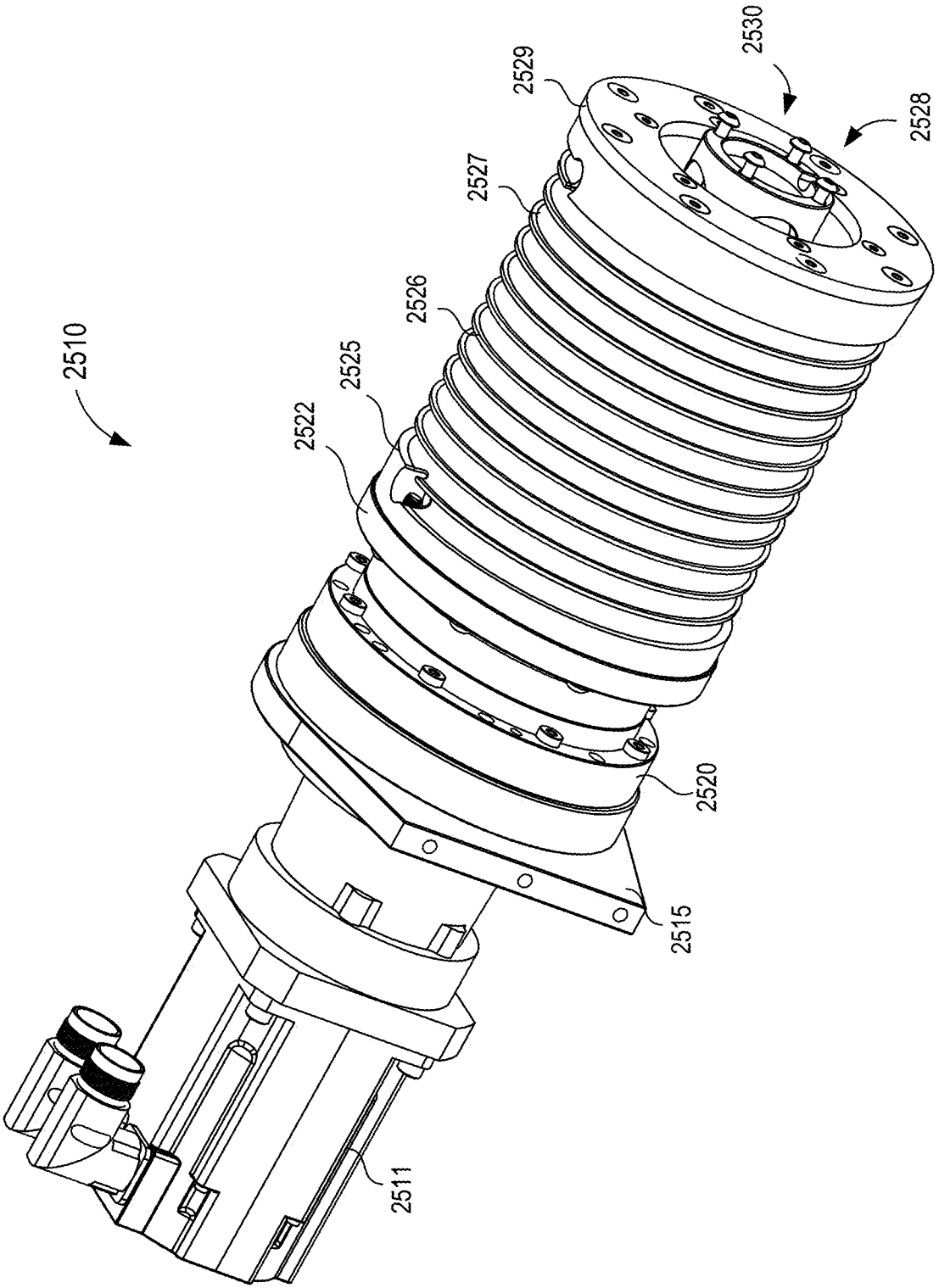

FIG. 29

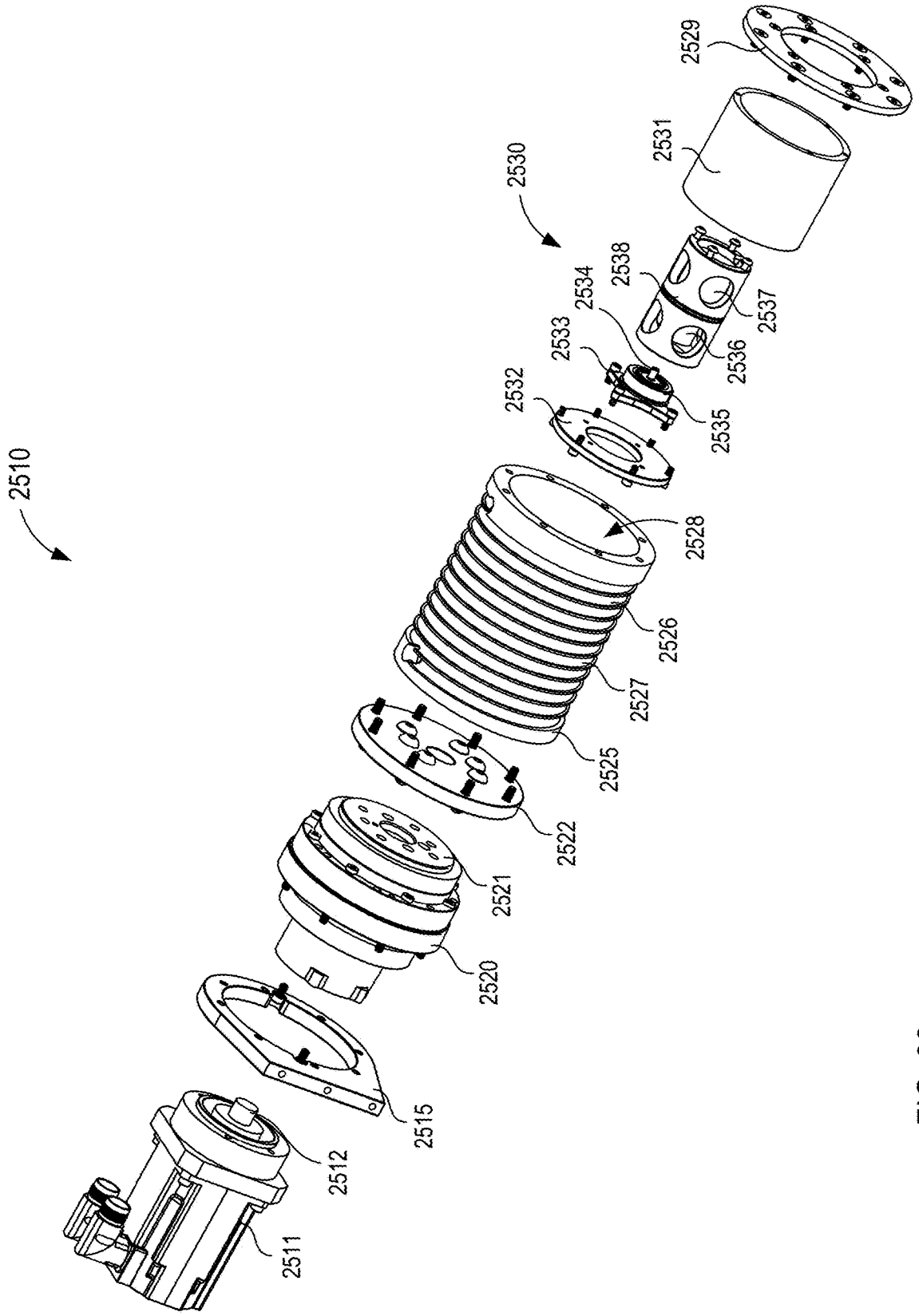
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FIG. 30

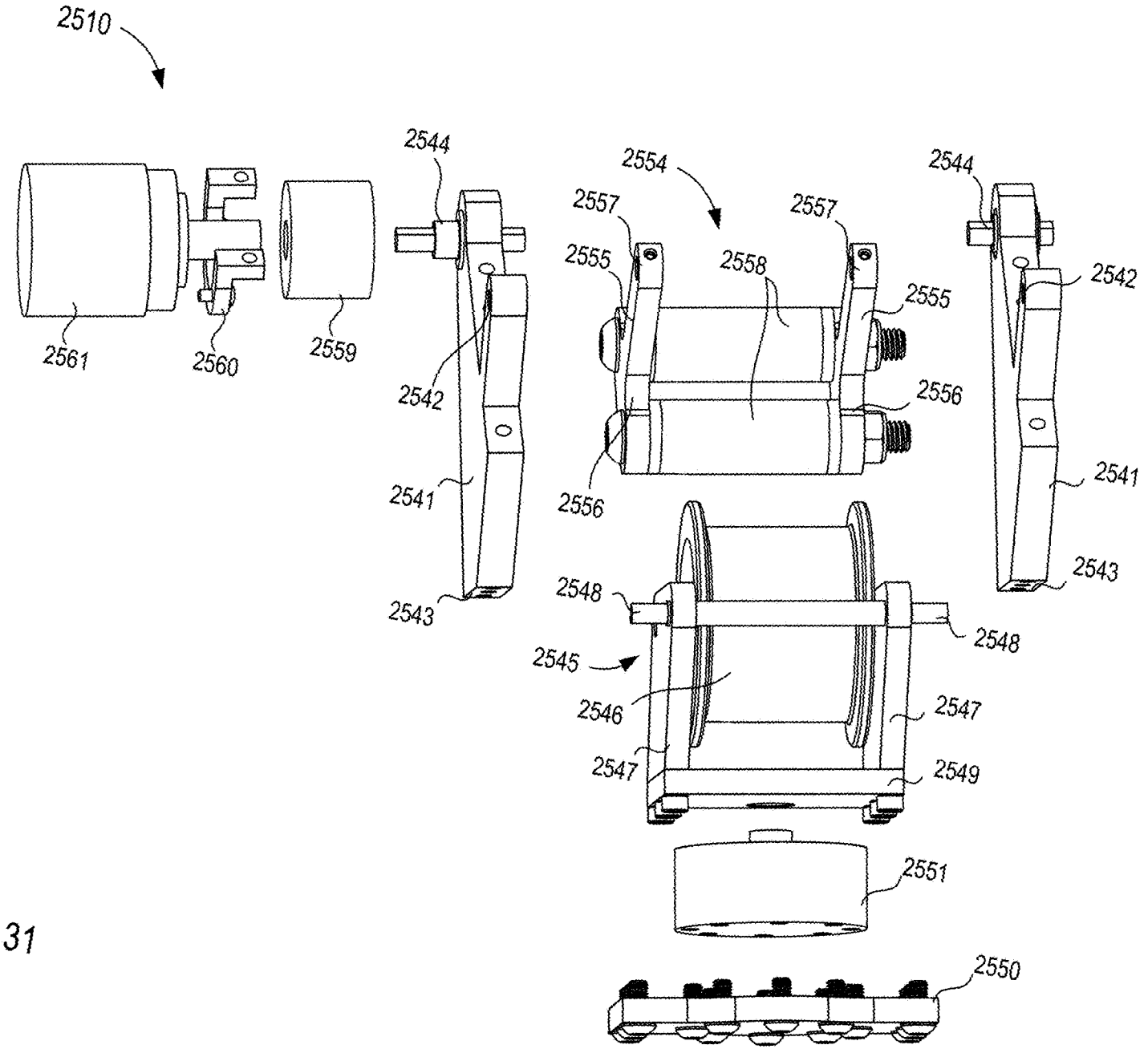
2510
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FIG. 31

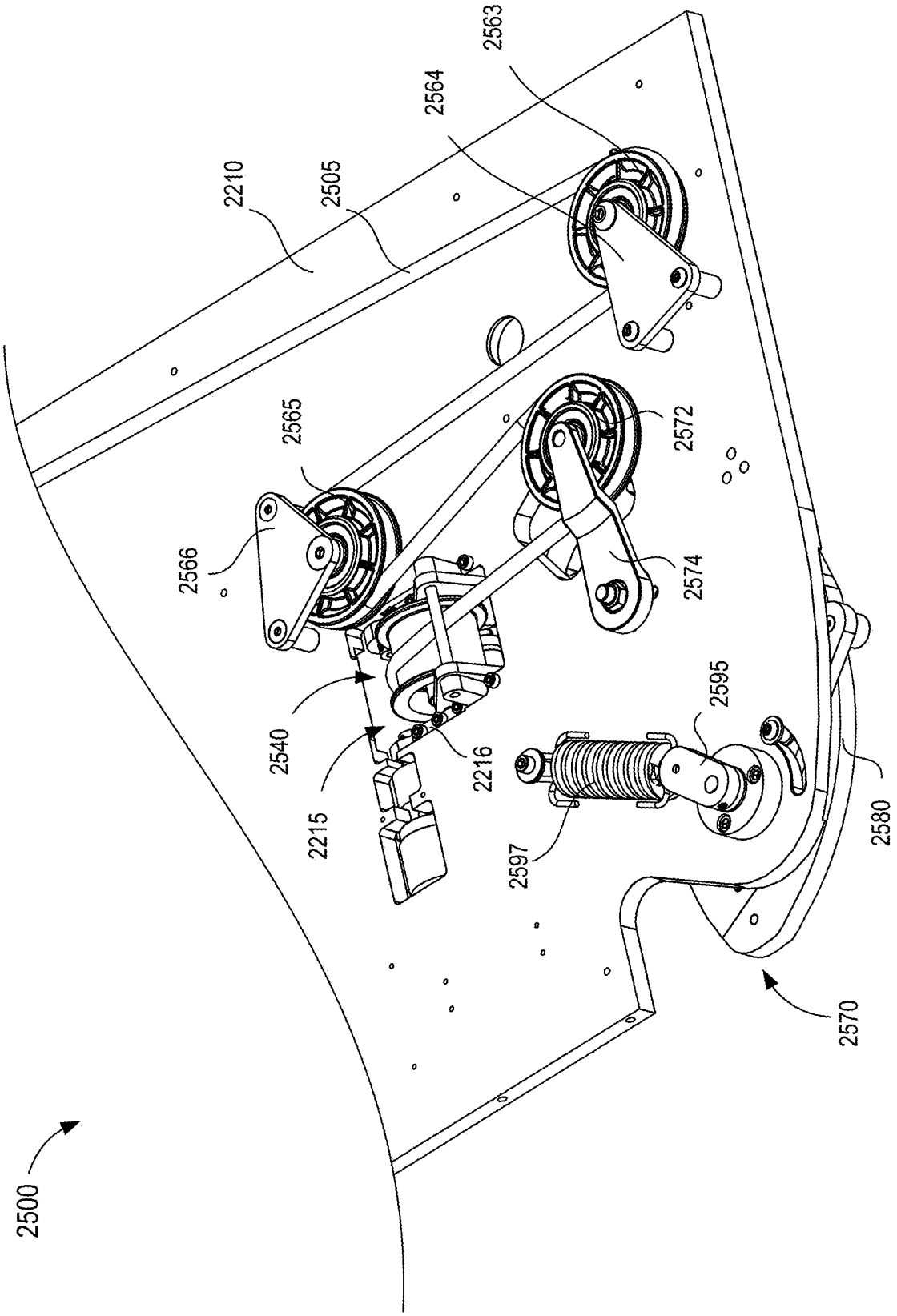
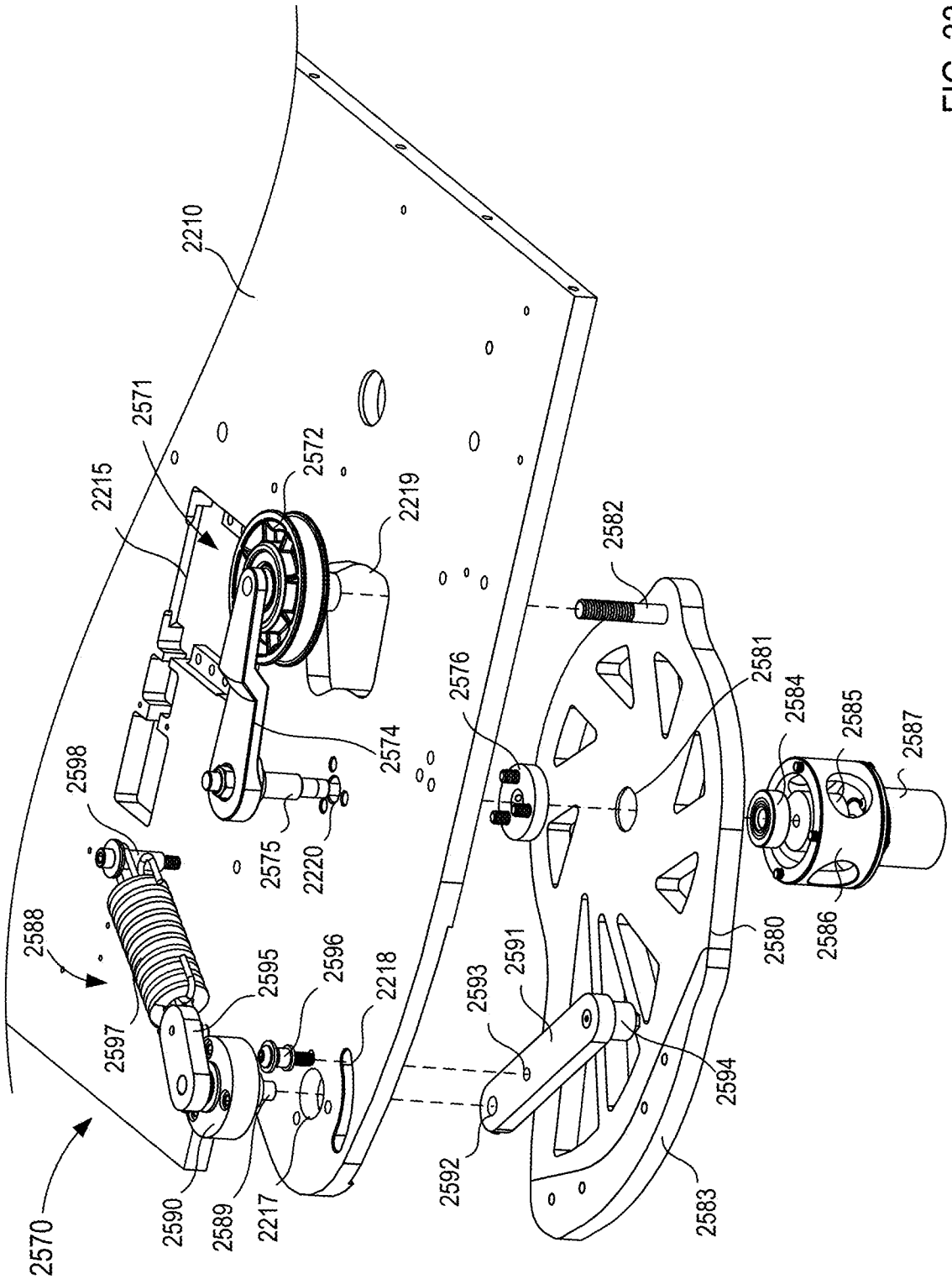

2563
2564
2210
2505
2565
2572
2566
2574
2595
2540
2216
2215
2597
2580
2570
2500

FIG. 32


2210
2571
2572
2215
2219
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2581
2576
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2598
2574
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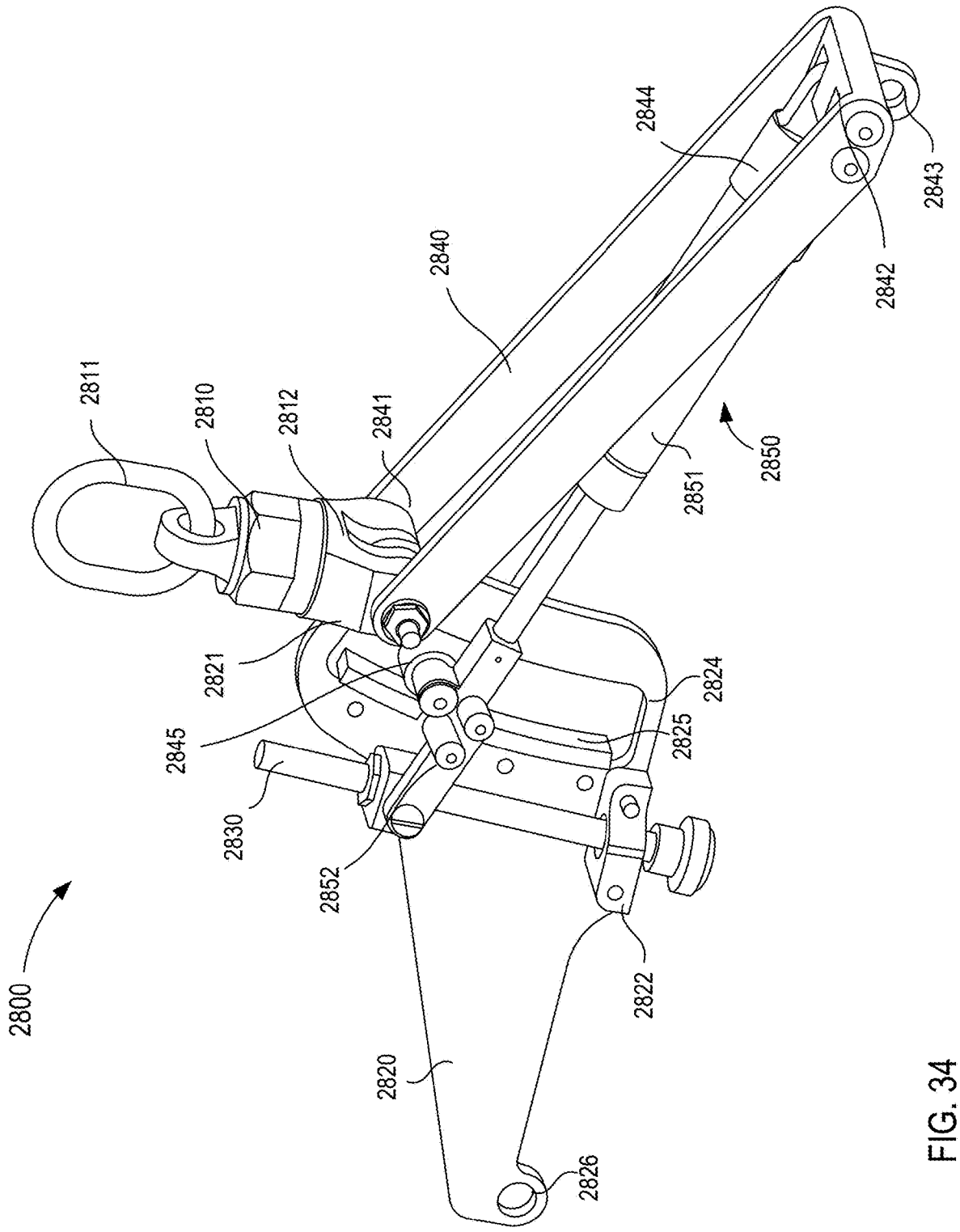
2220
2588
2595
2596
2218
2591
2593
2580
2586
2597
2594
2592
2583
2590
2589
2217
2570

FIG. 33


2800
2811
2810
2812
2841
2840
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2850
2851
2821
2824
2845
2825
2830
2852
2822
2820
2826

FIG. 34

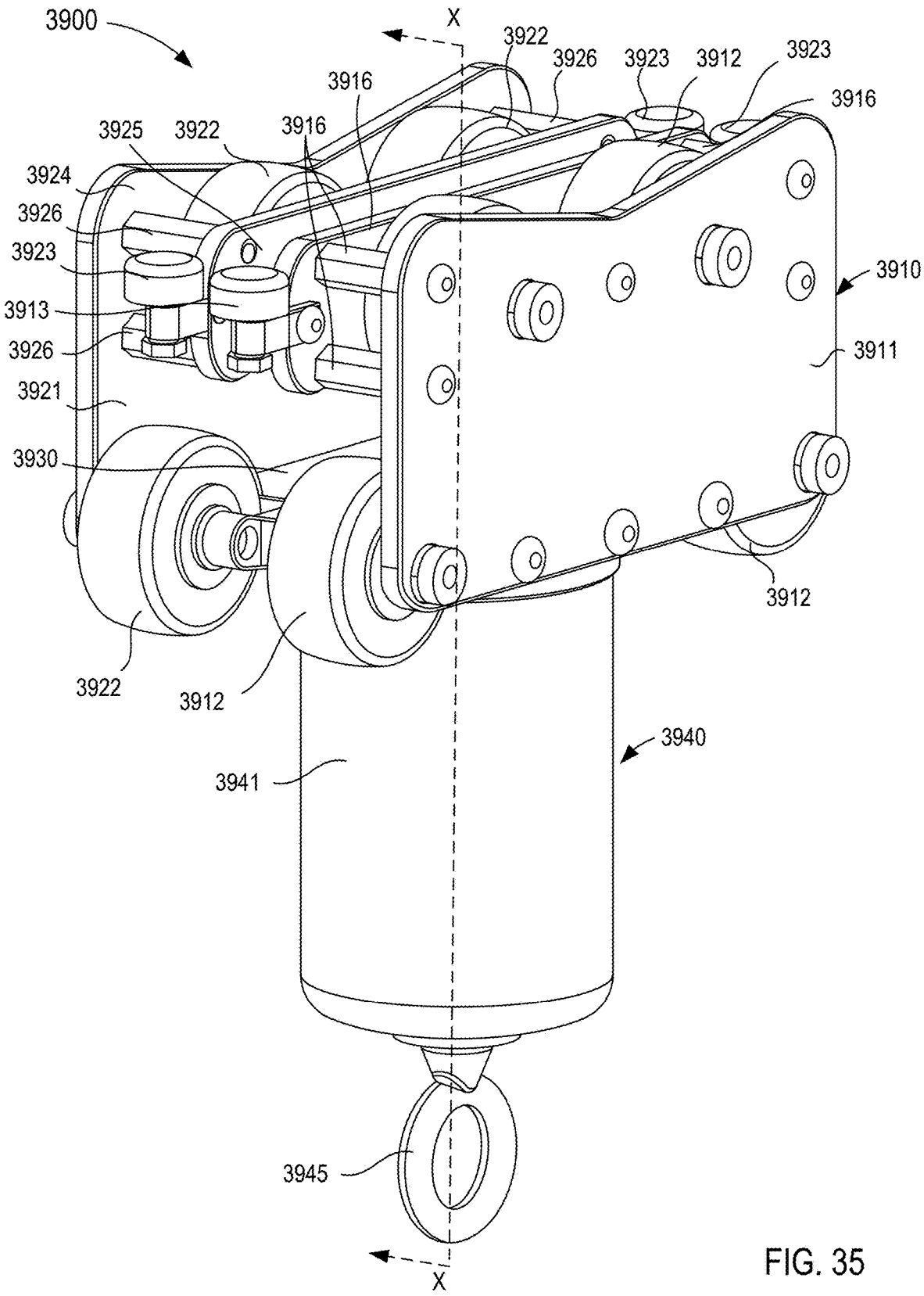

3900
X
3922
3926
3923
3912
3923
3916
3916
3925
3922
3916
3924
3926
3923
3913
3926
3921
3930
3910
3911
3912
3922
3912
3940
3941
3945
X

FIG. 35

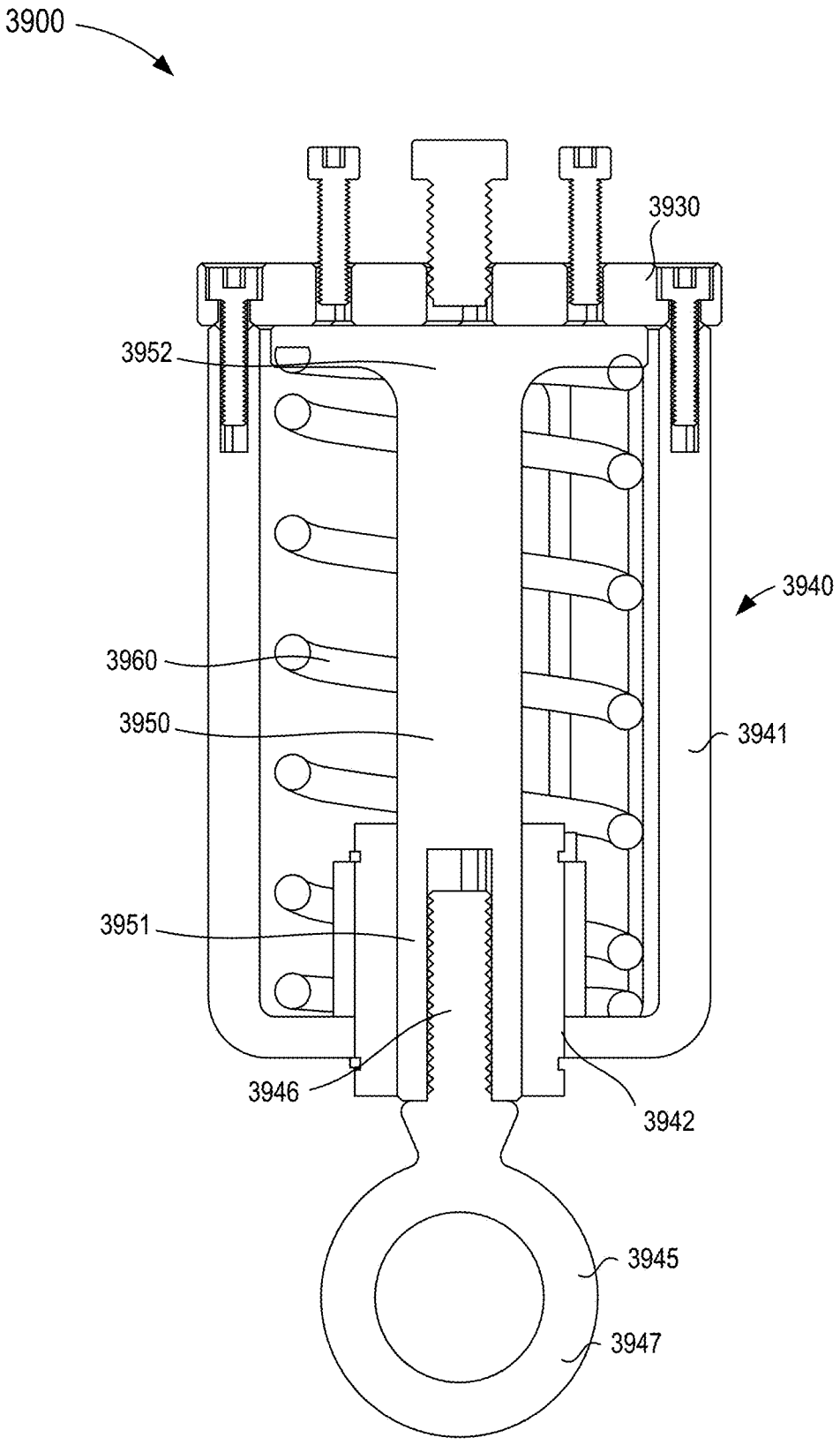


FIG. 36

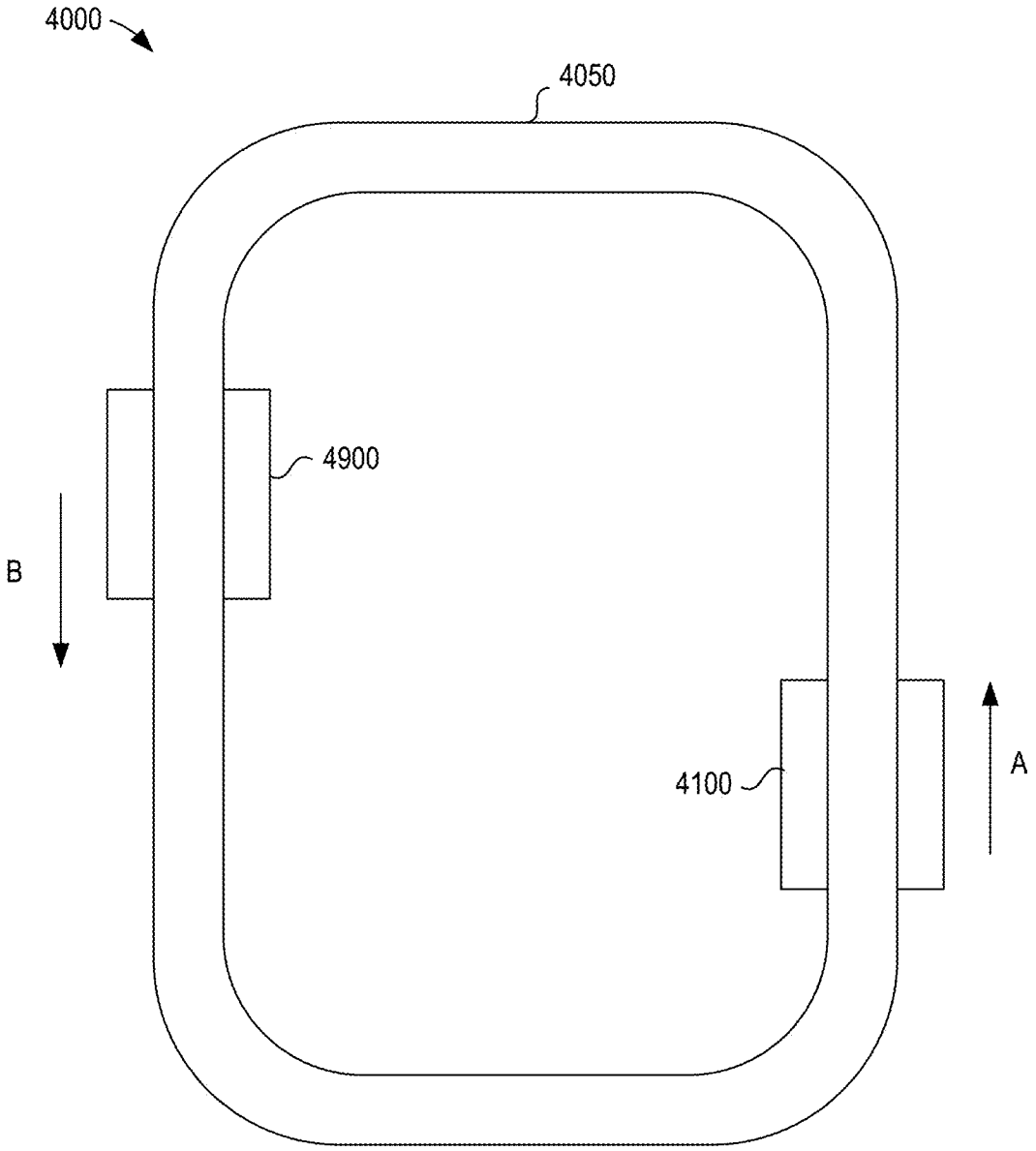


FIG. 37

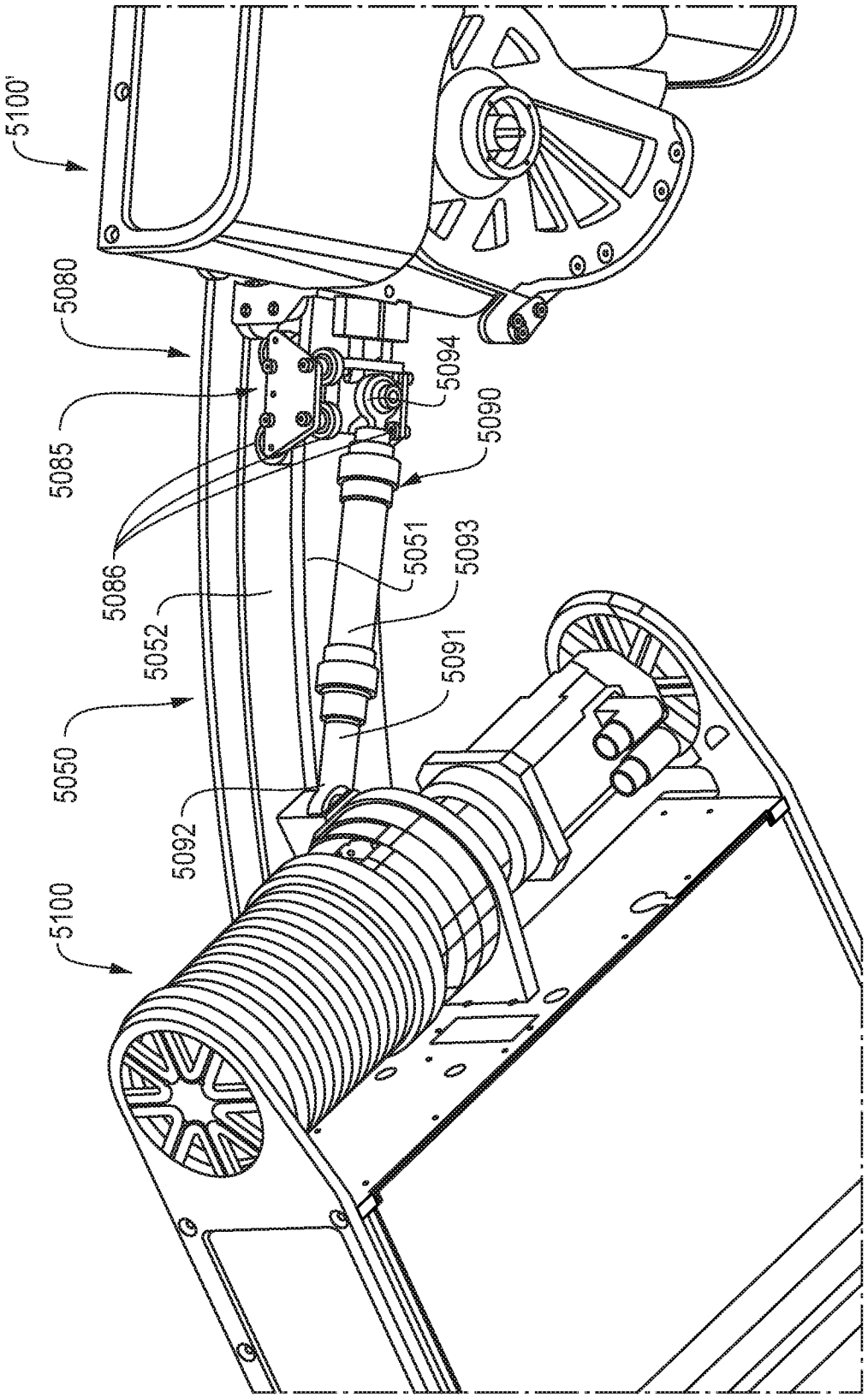

5100'
5080
5085
5086
5052
5050
5092
5100
5094
5090
5051
5093
5091

FIG. 38

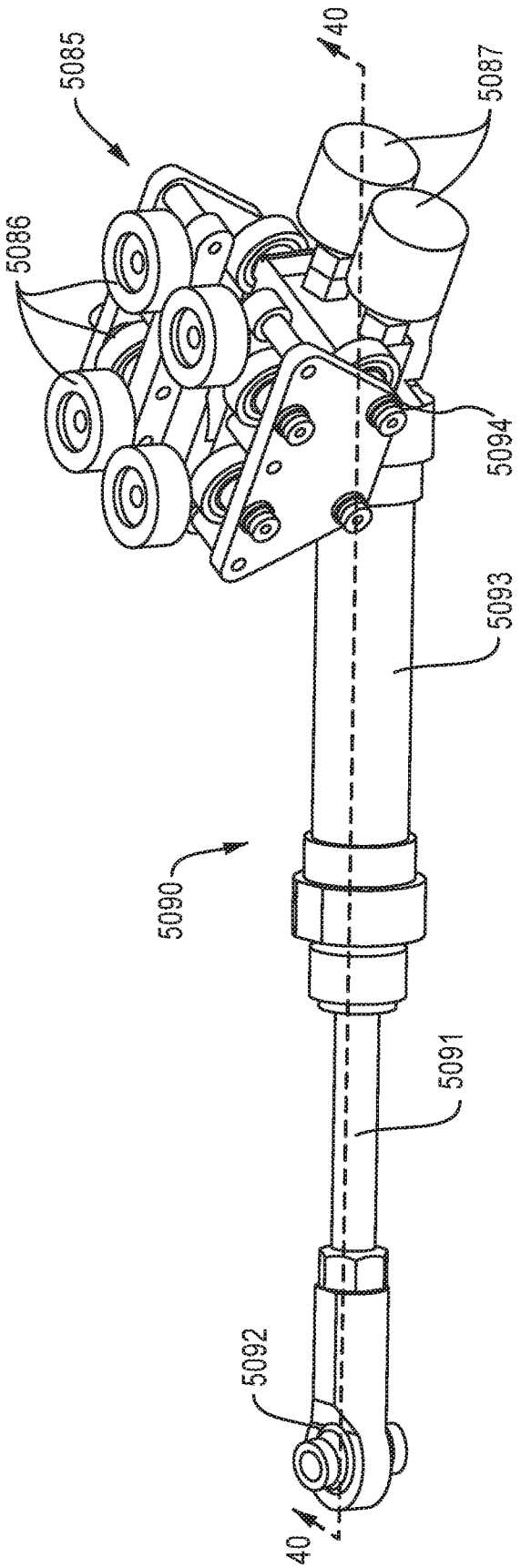

5085
40
5087
5086
5094
5093
5090
5091
5092
40

FIG. 39

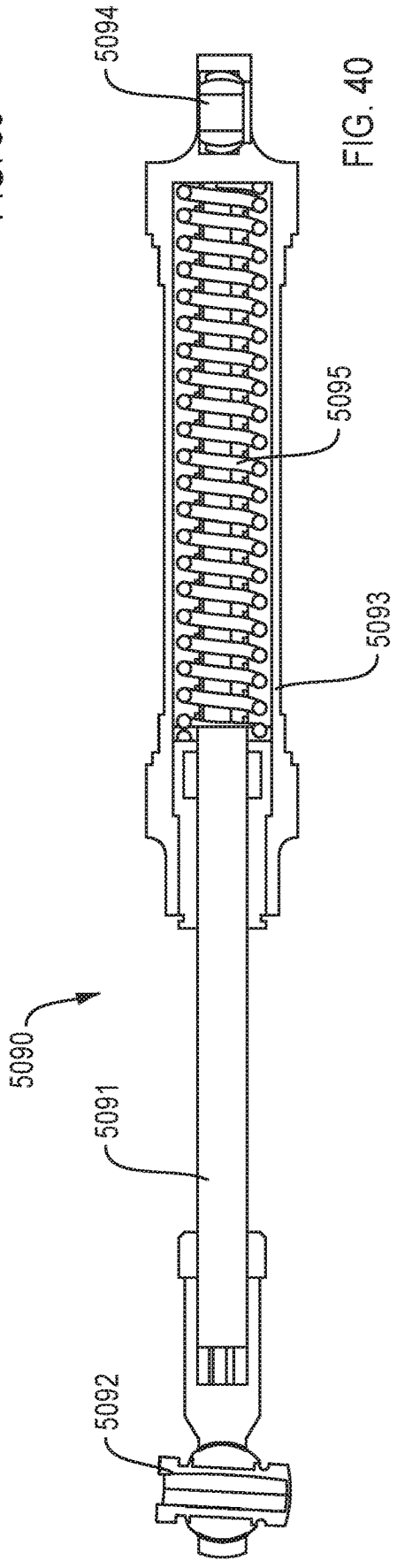

5094
5095
5093
5090
5091
5092

FIG. 40

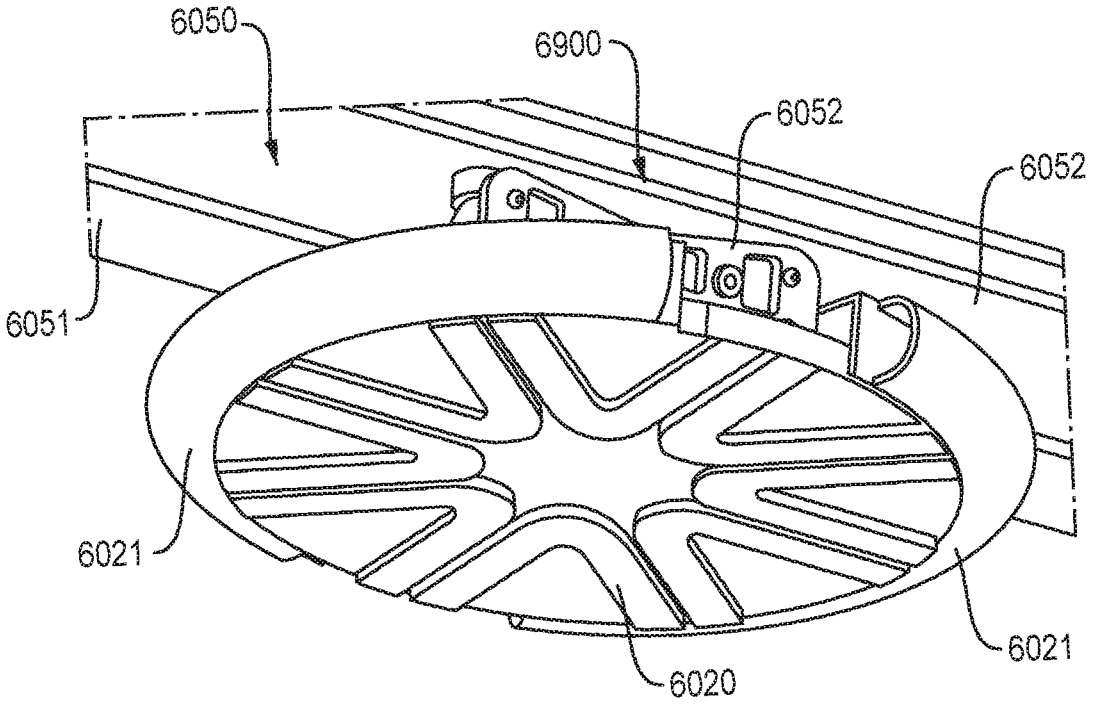

6050
6900
6052
6052
6051
6021
6021
6020

FIG. 41

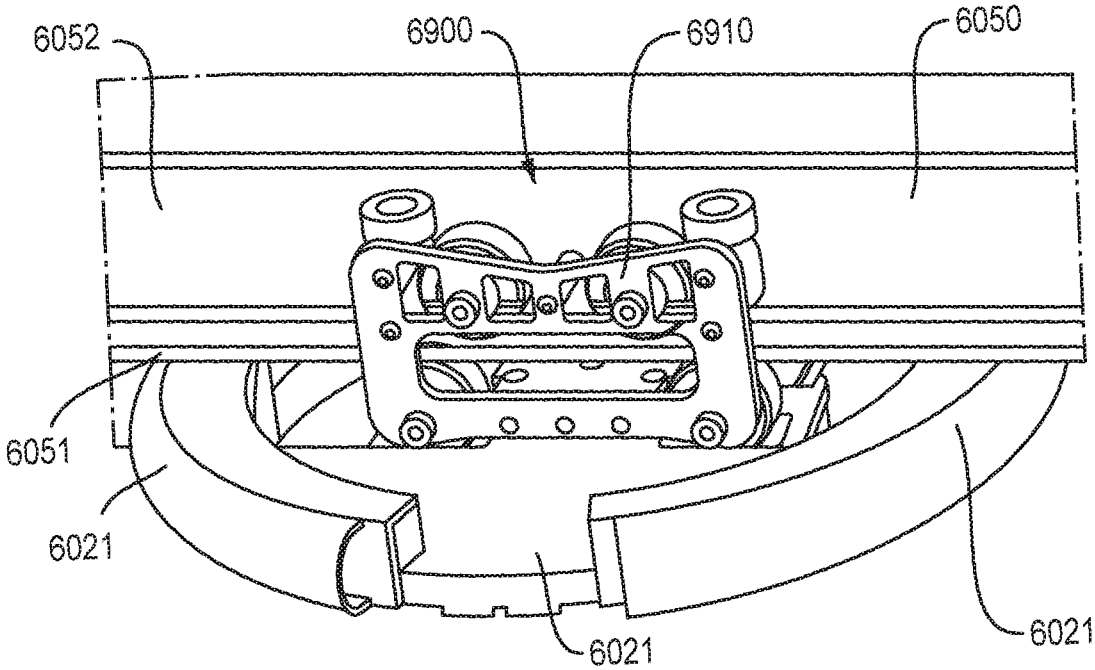

6052
6900
6910
6050
6051
6021
6021
6021

FIG. 42

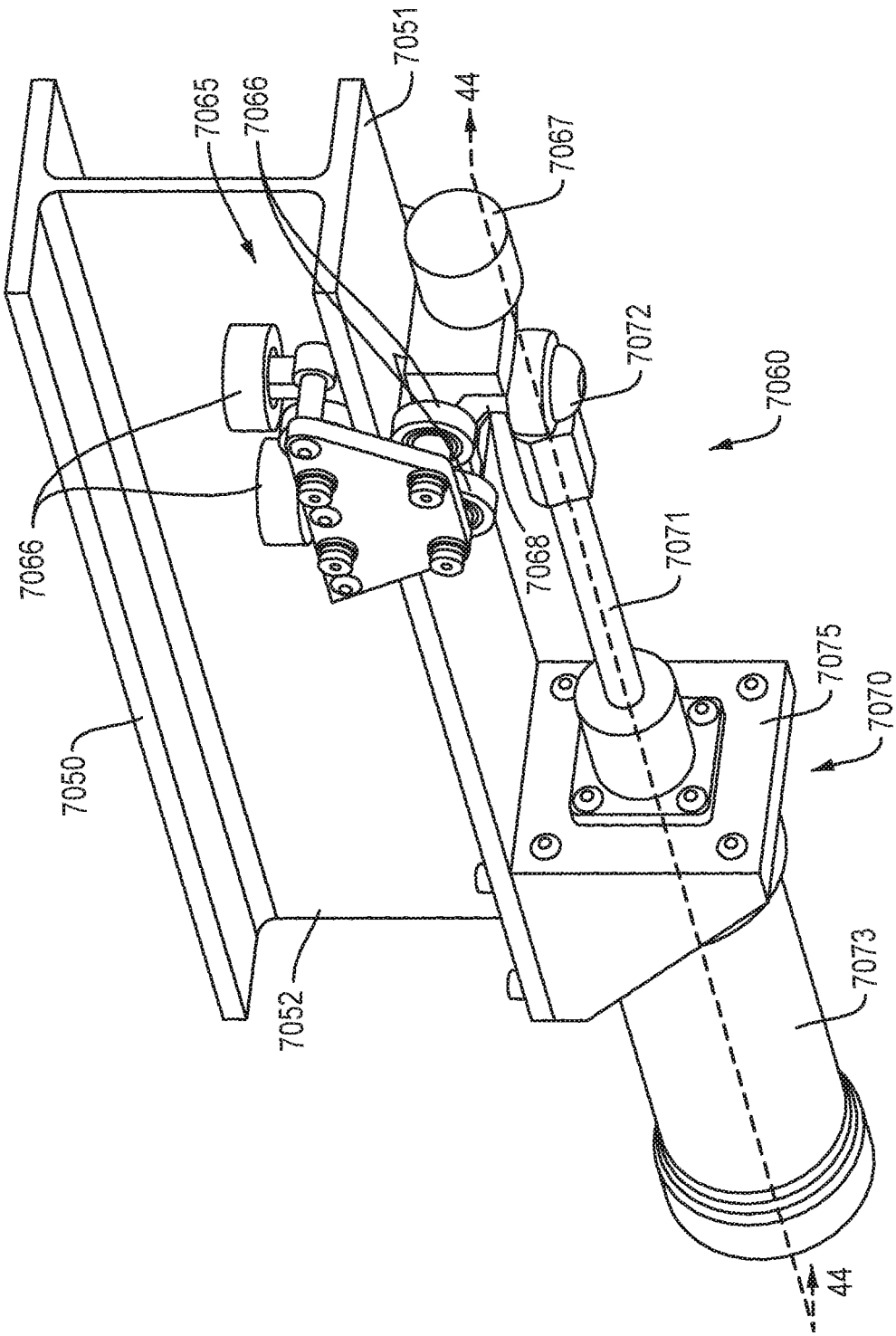

7051
7065
7066
44
7067
7072
7060
7066
7068
7071
7075
7070
7050
7073
7052
44

FIG. 43

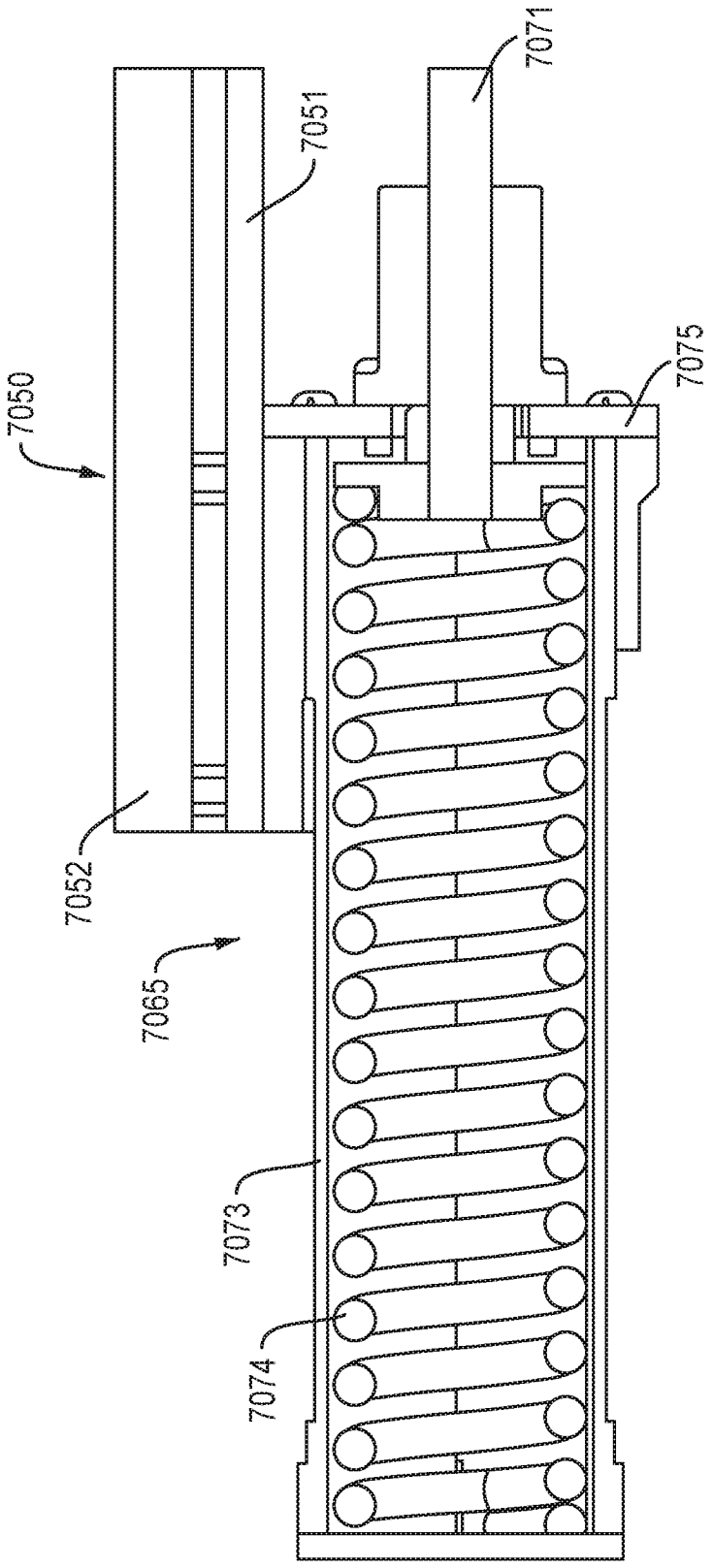


FIG. 44

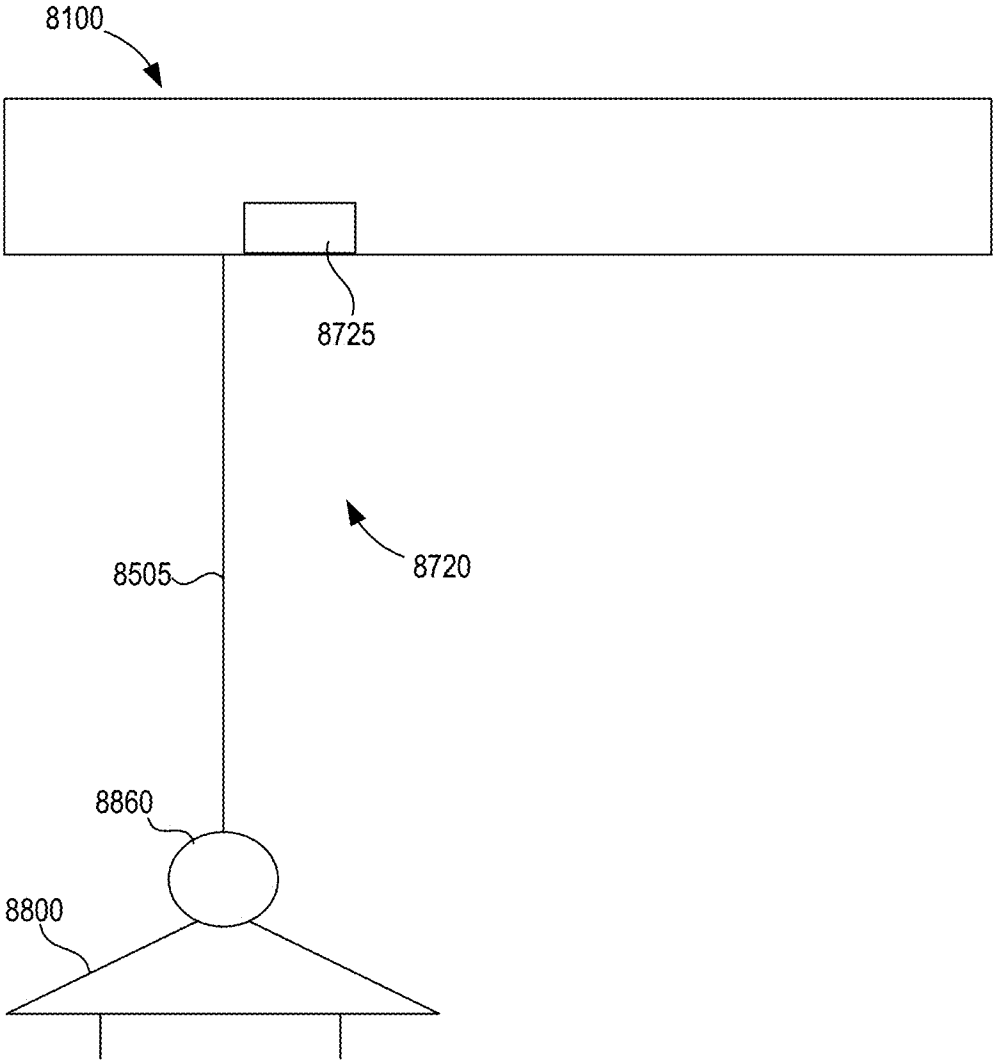


FIG. 45

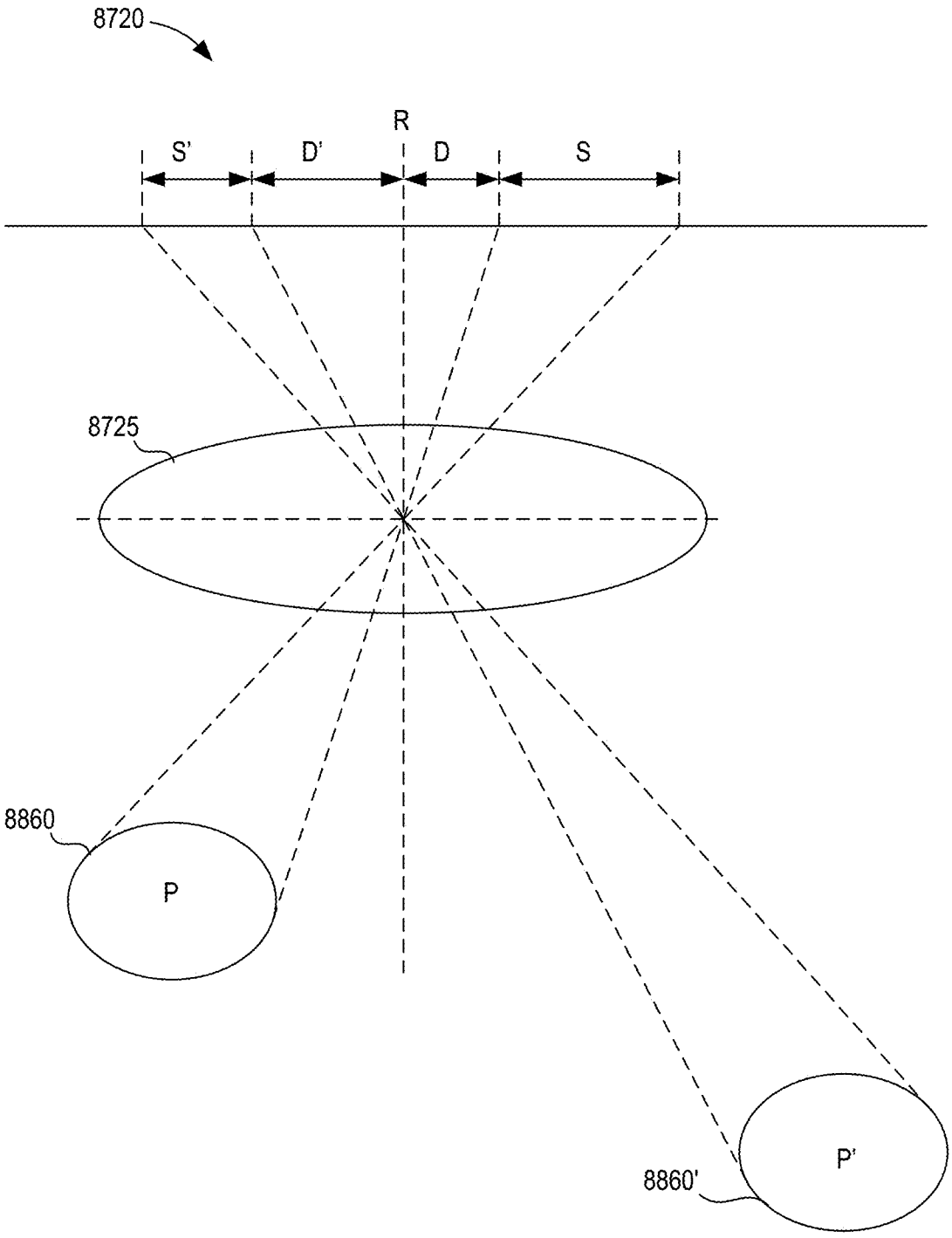


FIG. 46

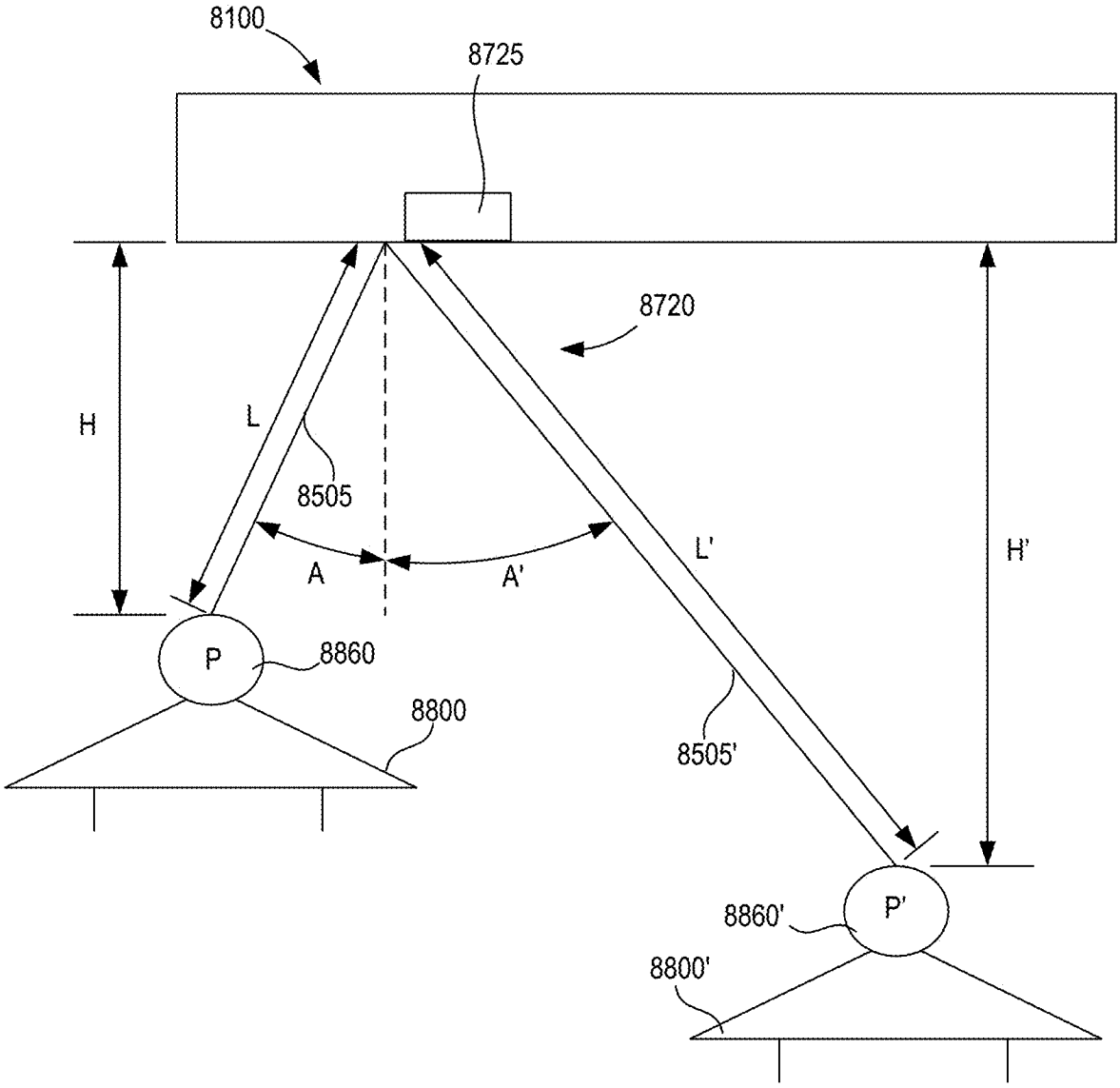


FIG. 47

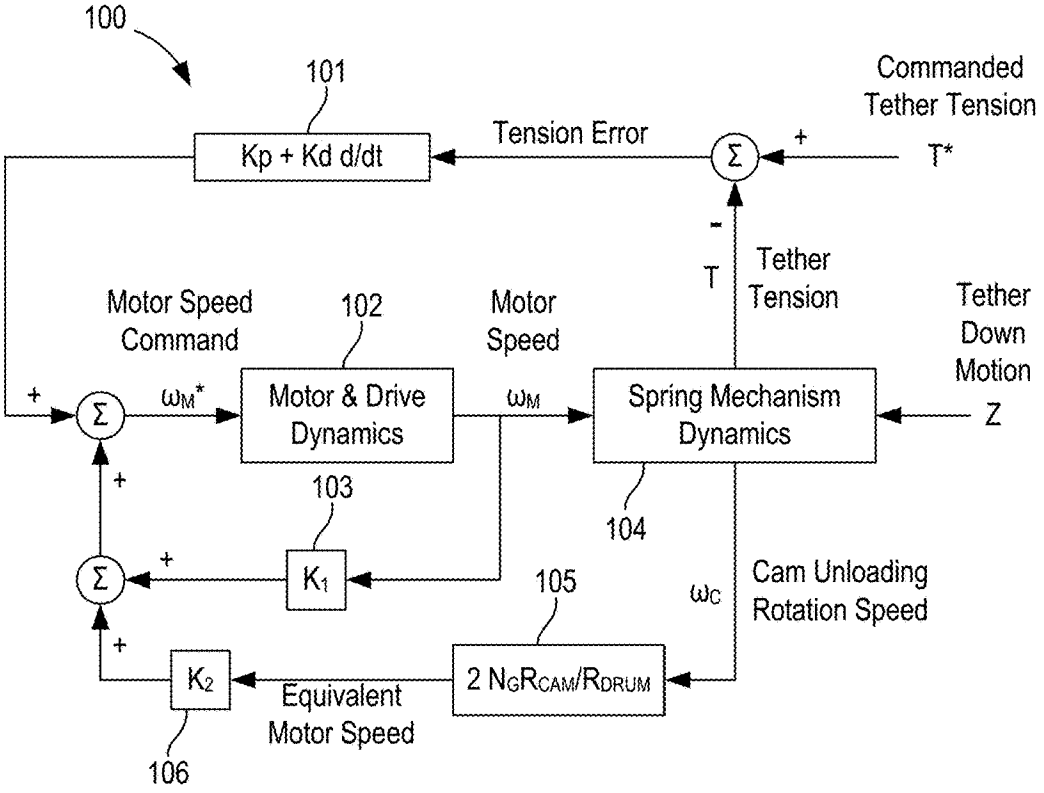

100
101
Kp + Kd d/dt
Tension Error
Commanded
Tether Tension
T*
Σ
+
-
T
Tether
Tension
Motor Speed
Command
102
Motor
Speed
Tether
Down
Motion
Z
ωM*
Motor & Drive
Dynamics
ωM
Spring Mechanism
Dynamics
103
104
K1
105
ωC
Cam Unloading
Rotation Speed
2 NGRCAM/RDRUM
K2
Equivalent
Motor Speed
106

FIG. 48

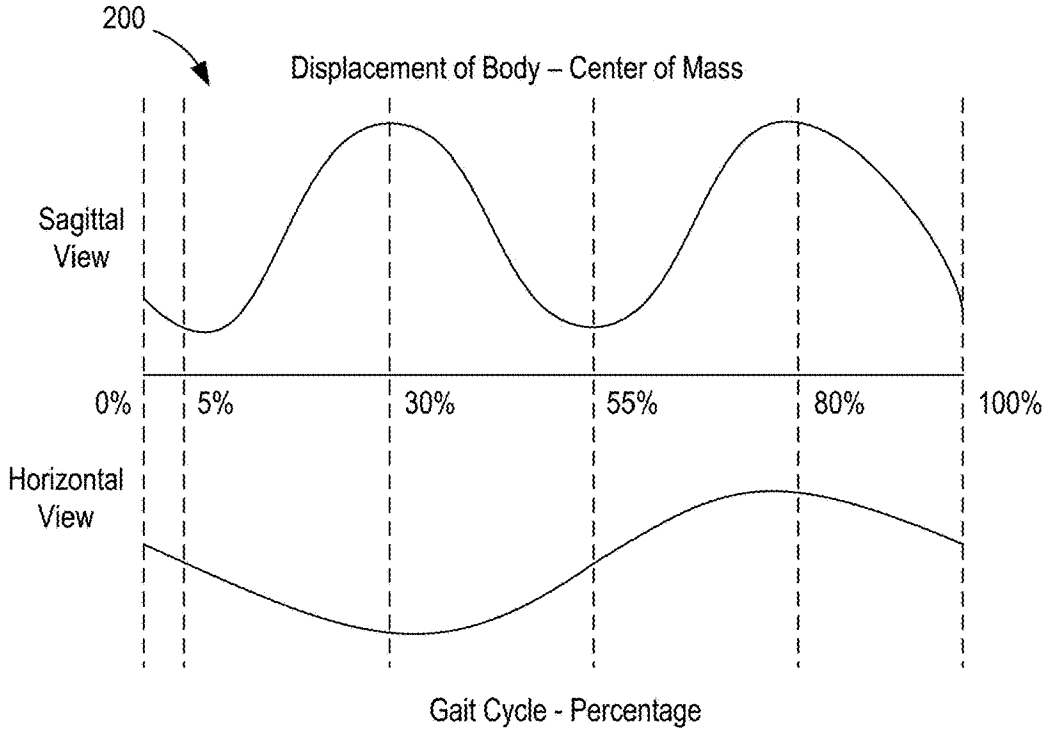

200
Displacement of Body – Center of Mass
Sagittal
View
0%
5%
30%
55%
80%
100%
Horizontal
View
Gait Cycle - Percentage

FIG. 49

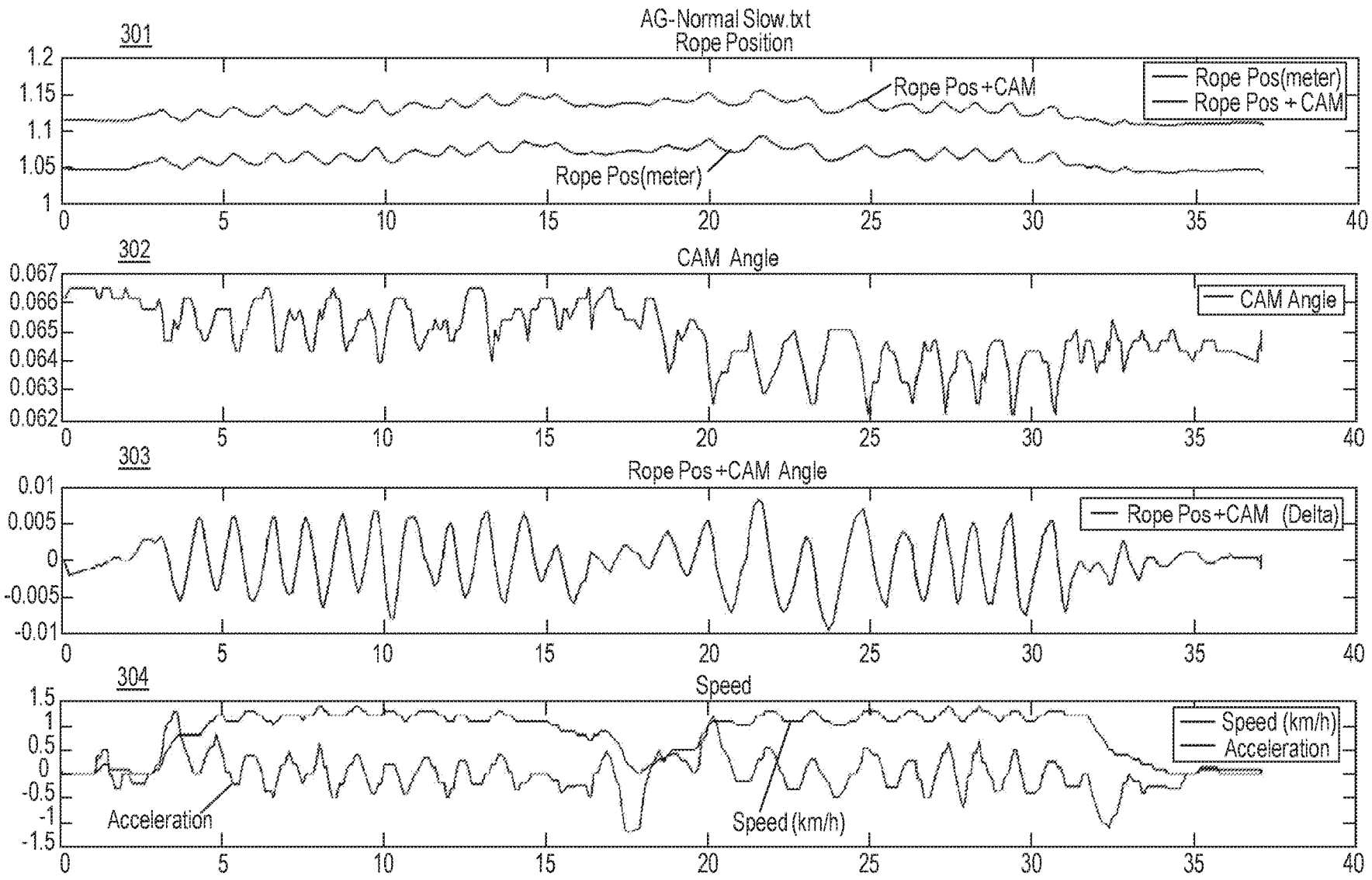

301
AG-Normal Slow.txt
Rope Position
Rope Pos+CAM
Rope Pos(meter)
Rope Pos(meter)
Rope Pos + CAM
302
CAM Angle
CAM Angle
303
Rope Pos+CAM Angle
Rope Pos+CAM (Delta)
304
Speed
Acceleration
Speed (km/h)
Speed (km/h)
Acceleration

FIG. 50

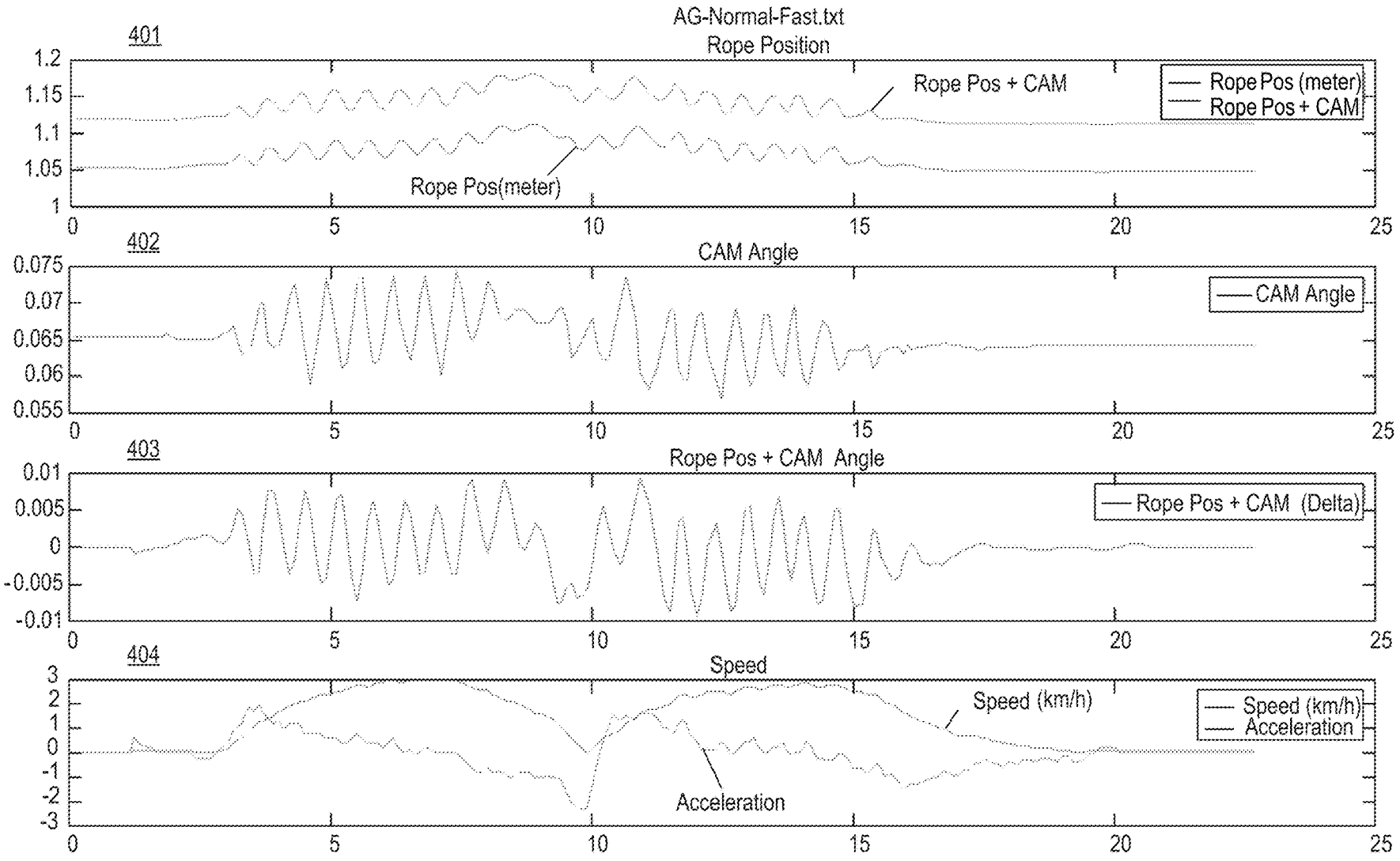

AG-Normal-Fast.txt
401
Rope Position
Rope Pos + CAM
Rope Pos (meter)
Rope Pos + CAM
Rope Pos(meter)
1.2
1.15
1.1
1.05
1
0
5
10
15
20
25
402
CAM Angle
CAM Angle
0.075
0.07
0.065
0.06
0.055
403
Rope Pos + CAM Angle
Rope Pos + CAM (Delta)
0.01
0.005
0
-0.005
-0.01
404
Speed
Speed (km/h)
Speed (km/h)
Acceleration
Acceleration
3
2
1
0
-1
-2
-3

FIG. 51

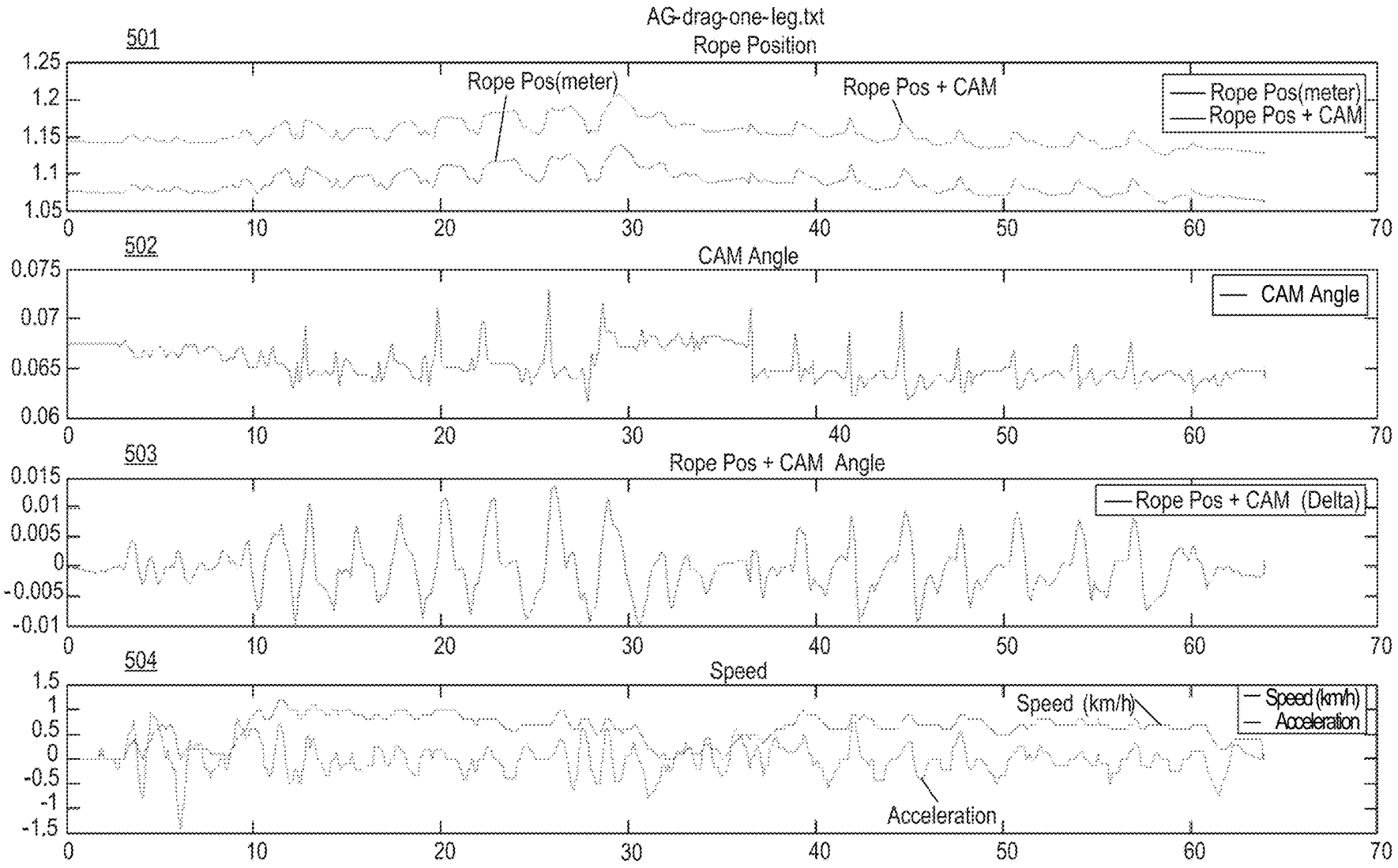

AG-drag-one-leg.txt
501
Rope Position
Rope Pos(meter)
Rope Pos + CAM
Rope Pos(meter)
Rope Pos + CAM
1.25
1.2
1.15
1.1
1.05
0
10
20
30
40
50
60
70
502
CAM Angle
CAM Angle
0.075
0.07
0.065
0.06
503
Rope Pos + CAM Angle
Rope Pos + CAM (Delta)
0.015
0.01
0.005
0
-0.005
-0.01
504
Speed
Speed (km/h)
Acceleration
Speed (km/h)
Acceleration
1.5
1
0.5
0
-0.5
-1
-1.5

FIG. 52

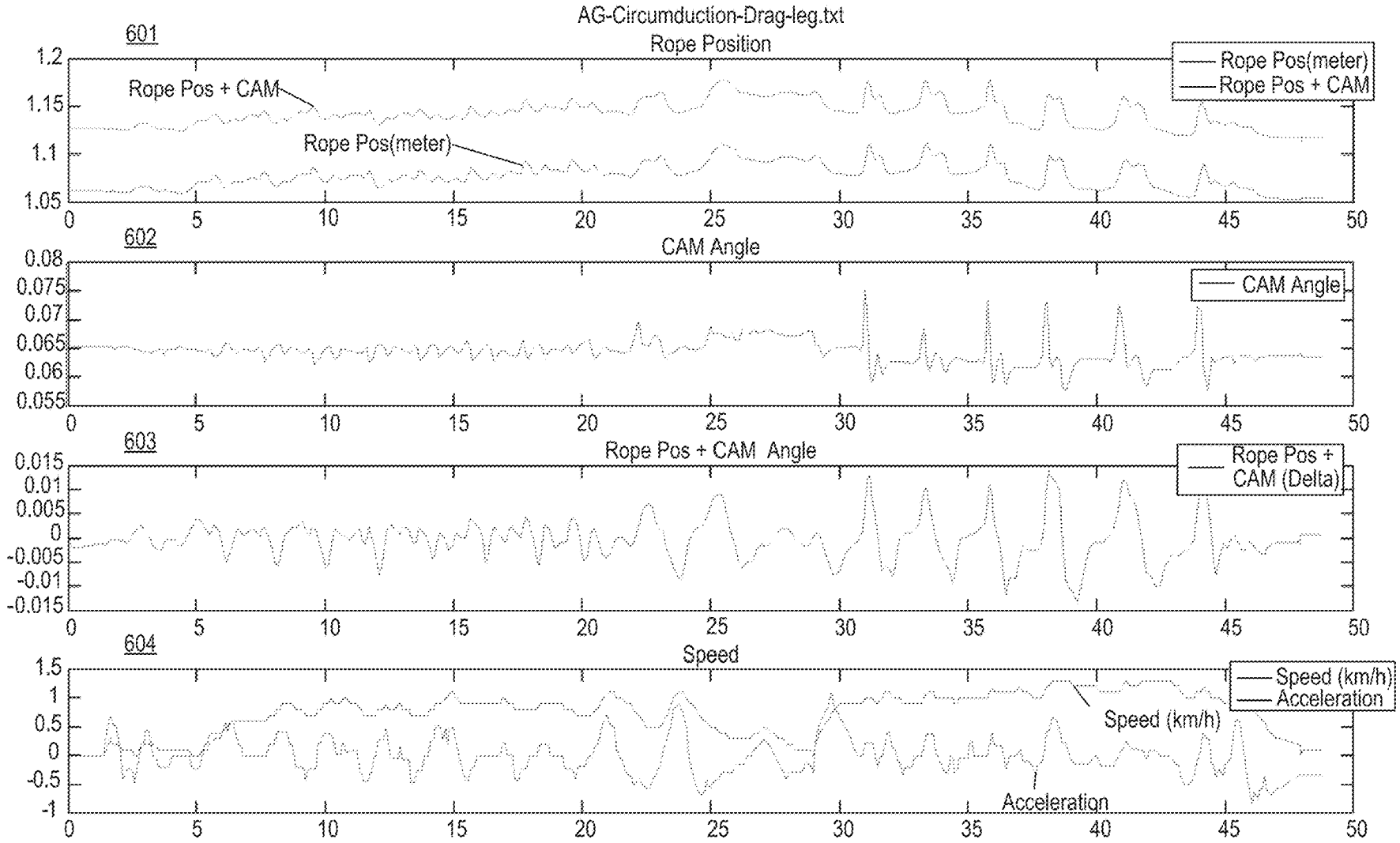

AG-Circumduction-Drag-leg.txt
601
Rope Position
Rope Pos + CAM
Rope Pos(meter)
Rope Pos(meter)
Rope Pos + CAM
602
CAM Angle
CAM Angle
603
Rope Pos + CAM Angle
Rope Pos + CAM (Delta)
604
Speed
Speed (km/h)
Acceleration
Speed (km/h)
Acceleration

FIG. 53

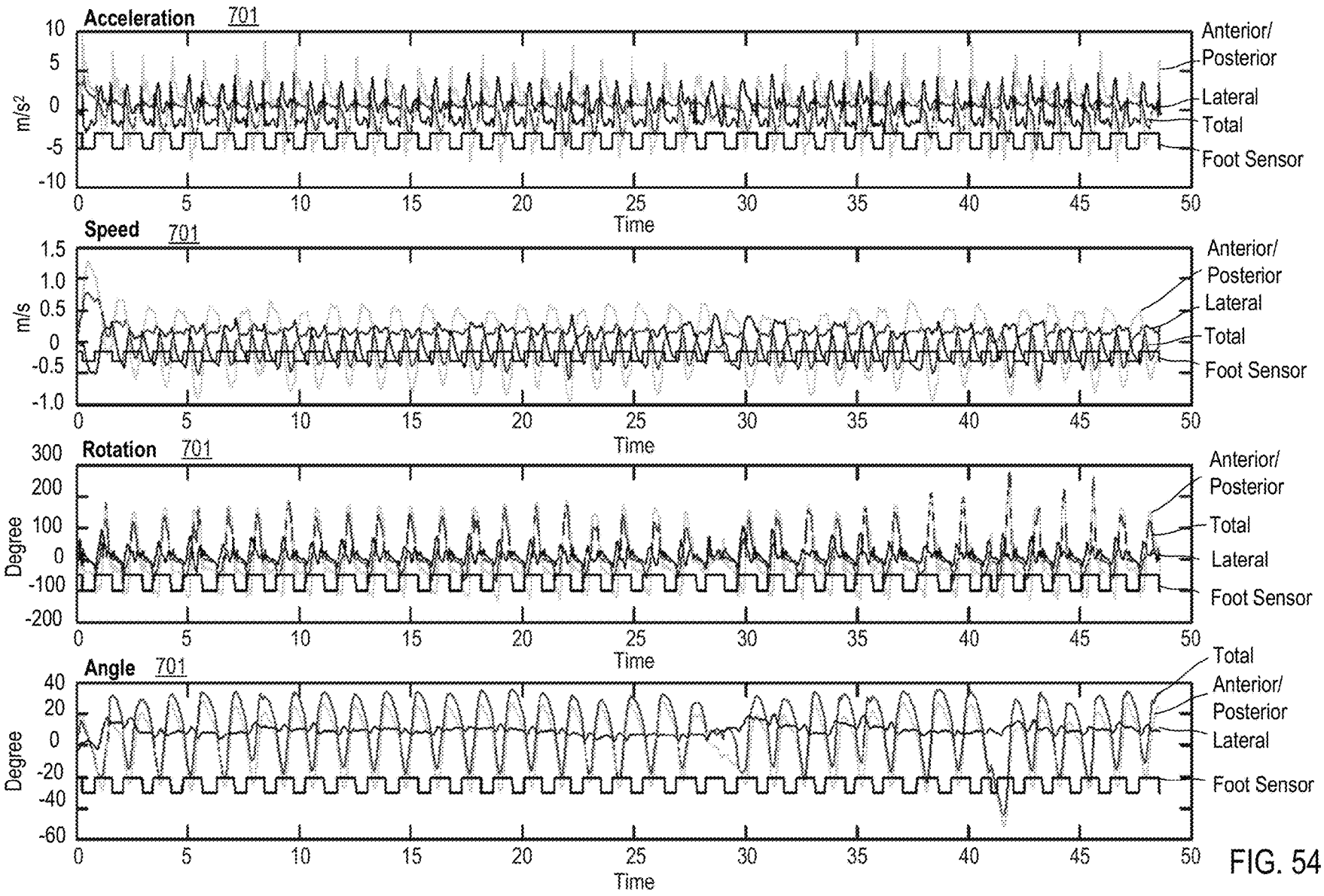
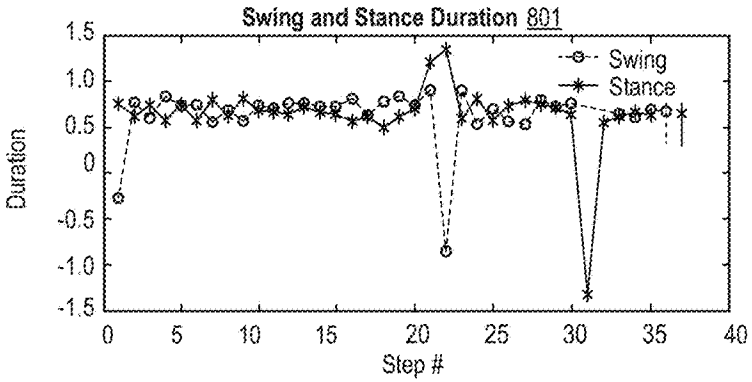
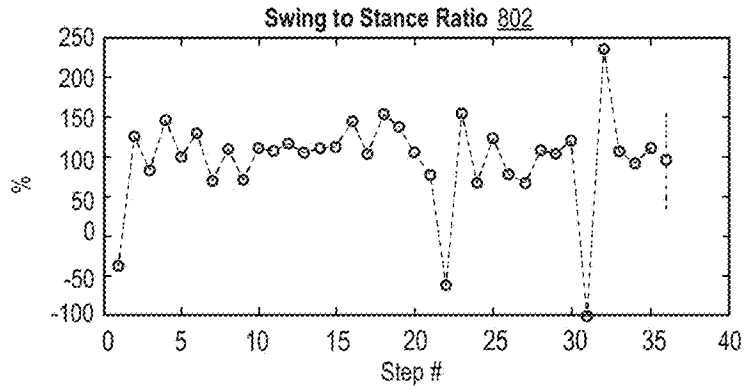
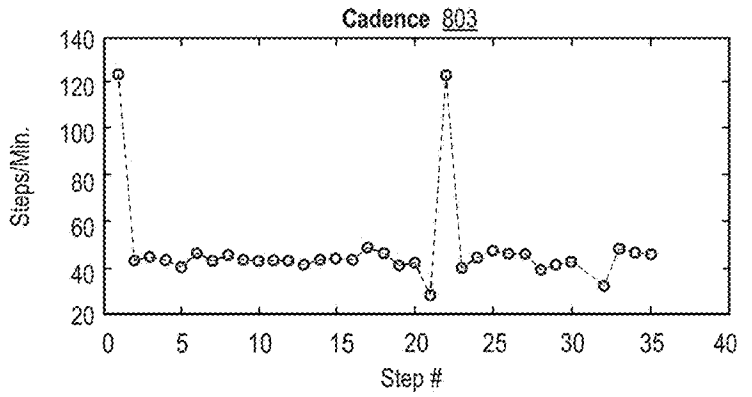
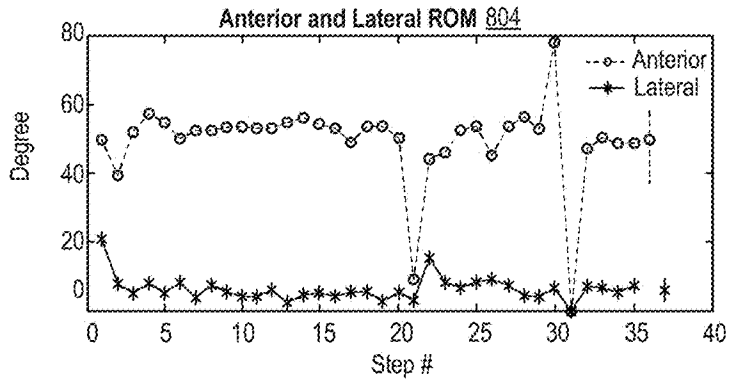

Acceleration 701
m/s²
10
5
0
-5
-10
0 5 10 15 20 25 30 35 40 45 50
Time
Anterior/ Posterior
Lateral
Total
Foot Sensor
Speed 701
m/s
1.5
1.0
0.5
0
-0.5
-1.0
0 5 10 15 20 25 30 35 40 45 50
Time
Anterior/ Posterior
Lateral
Total
Foot Sensor
Rotation 701
Degree
300
200
100
0
-100
-200
0 5 10 15 20 25 30 35 40 45 50
Time
Anterior/ Posterior
Total
Lateral
Foot Sensor
Angle 701
Degree
40
20
0
-20
-40
-60
0 5 10 15 20 25 30 35 40 45 50
Time
Total
Anterior/ Posterior
Lateral
Foot Sensor

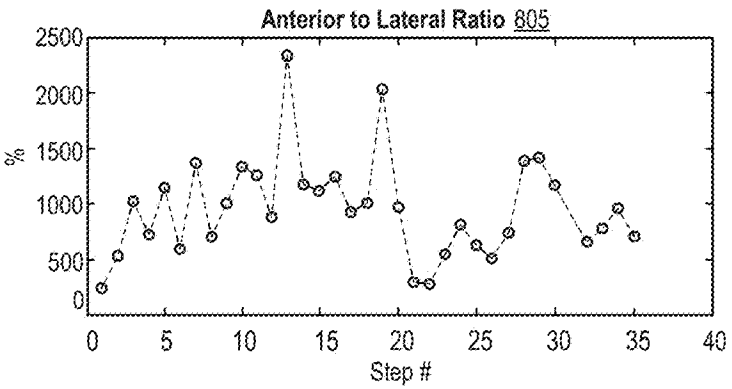
FIG. 54


Swing and Stance Duration 801
Swing
Stance
Duration
Step #


Swing to Stance Ratio 802
%
Step #


Cadence 803
Steps/Min.
Step #


Anterior and Lateral ROM 804
Anterior
Lateral
Degree
Step #


Anterior to Lateral Ratio 805
%
Step #

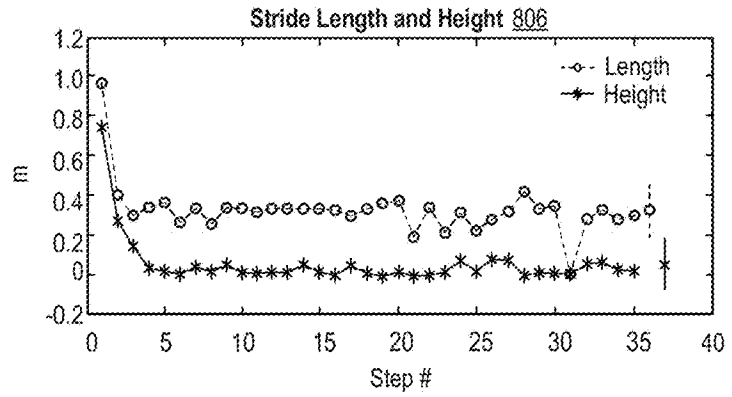

Stride Length and Height 806
Length
Height
m
Step #

FIG. 55

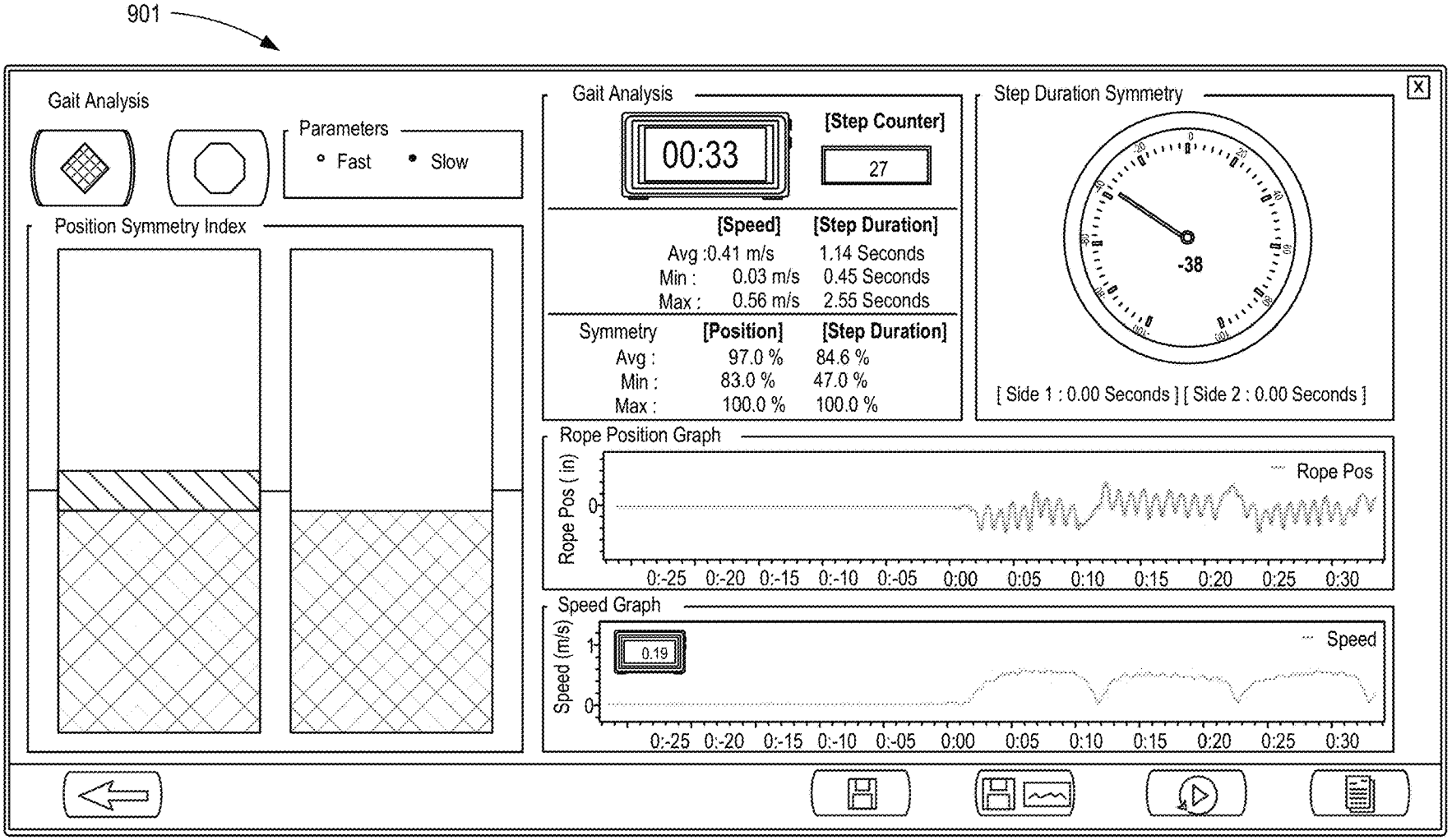

901
Gait Analysis
Parameters
Fast
Slow
Position Symmetry Index
Gait Analysis
00:33
[Step Counter]
27
[Speed]
[Step Duration]
Avg :0.41 m/s
1.14 Seconds
Min : 0.03 m/s
0.45 Seconds
Max : 0.56 m/s
2.55 Seconds
Symmetry
[Position]
[Step Duration]
Avg : 97.0 %
84.6 %
Min : 83.0 %
47.0 %
Max : 100.0 %
100.0 %
Step Duration Symmetry
-38
[Side 1 : 0.00 Seconds] [Side 2 : 0.00 Seconds]
Rope Position Graph
Rope Pos (in)
Rope Pos
0:-25 0:-20 0:-15 0:-10 0:-05 0:00 0:05 0:10 0:15 0:20 0:25 0:30
Speed Graph
Speed (m/s)
0.19
Speed
0:-25 0:-20 0:-15 0:-10 0:-05 0:00 0:05 0:10 0:15 0:20 0:25 0:30

FIG. 56

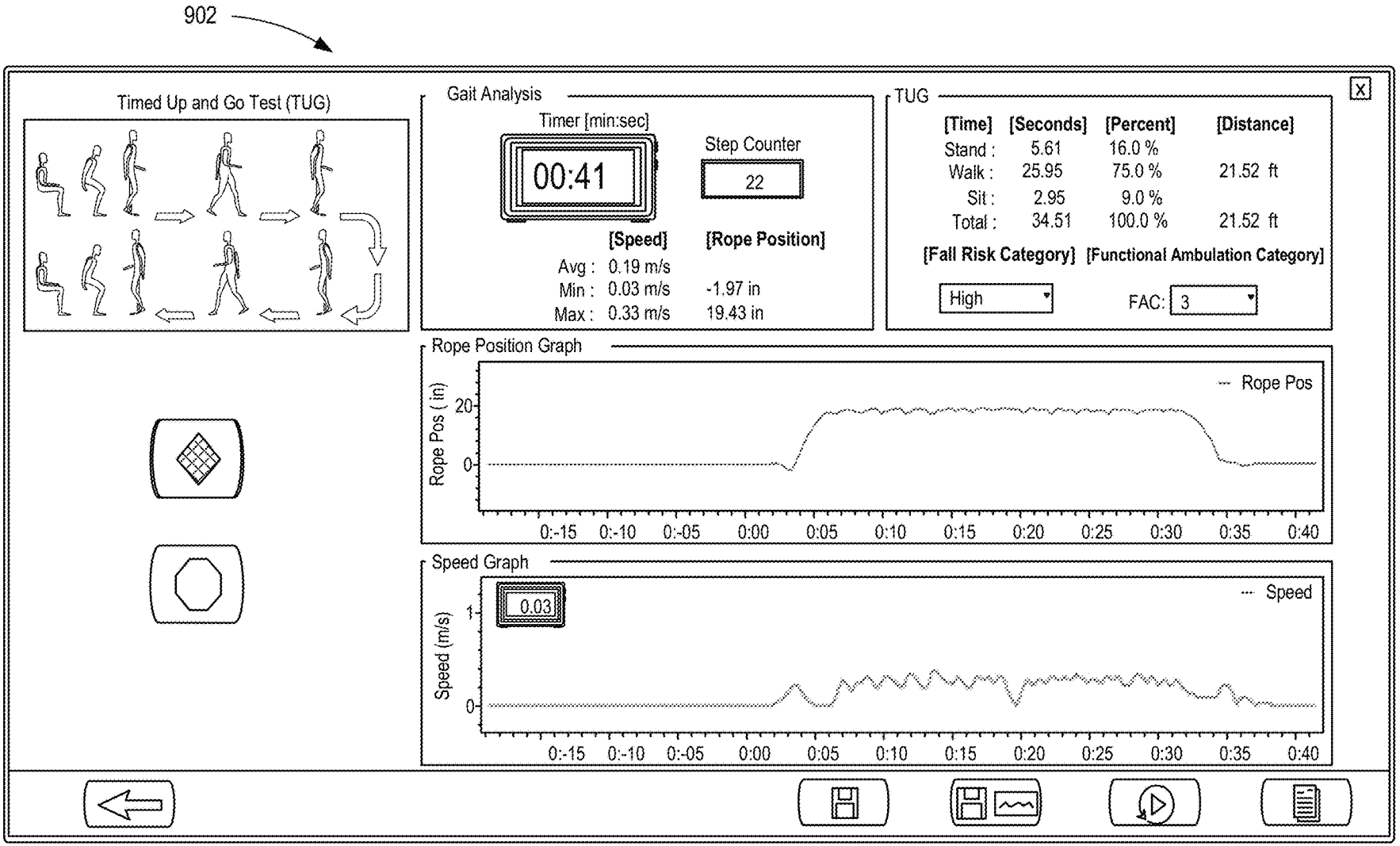

902
Timed Up and Go Test (TUG)
Gait Analysis
Timer [min:sec]
00:41
Step Counter
22
[Speed]
[Rope Position]
Avg : 0.19 m/s
Min : 0.03 m/s -1.97 in
Max : 0.33 m/s 19.43 in
TUG
[Time] [Seconds] [Percent] [Distance]
Stand : 5.61 16.0 %
Walk : 25.95 75.0 % 21.52 ft
Sit : 2.95 9.0 %
Total : 34.51 100.0 % 21.52 ft
[Fall Risk Category] [Functional Ambulation Category]
High
FAC: 3
Rope Position Graph
Rope Pos
Rope Pos (in)
20
0
0:-15 0:-10 0:-05 0:00 0:05 0:10 0:15 0:20 0:25 0:30 0:35 0:40
Speed Graph
Speed
0.03
Speed (m/s)
1
0
0:-15 0:-10 0:-05 0:00 0:05 0:10 0:15 0:20 0:25 0:30 0:35 0:40

FIG. 57

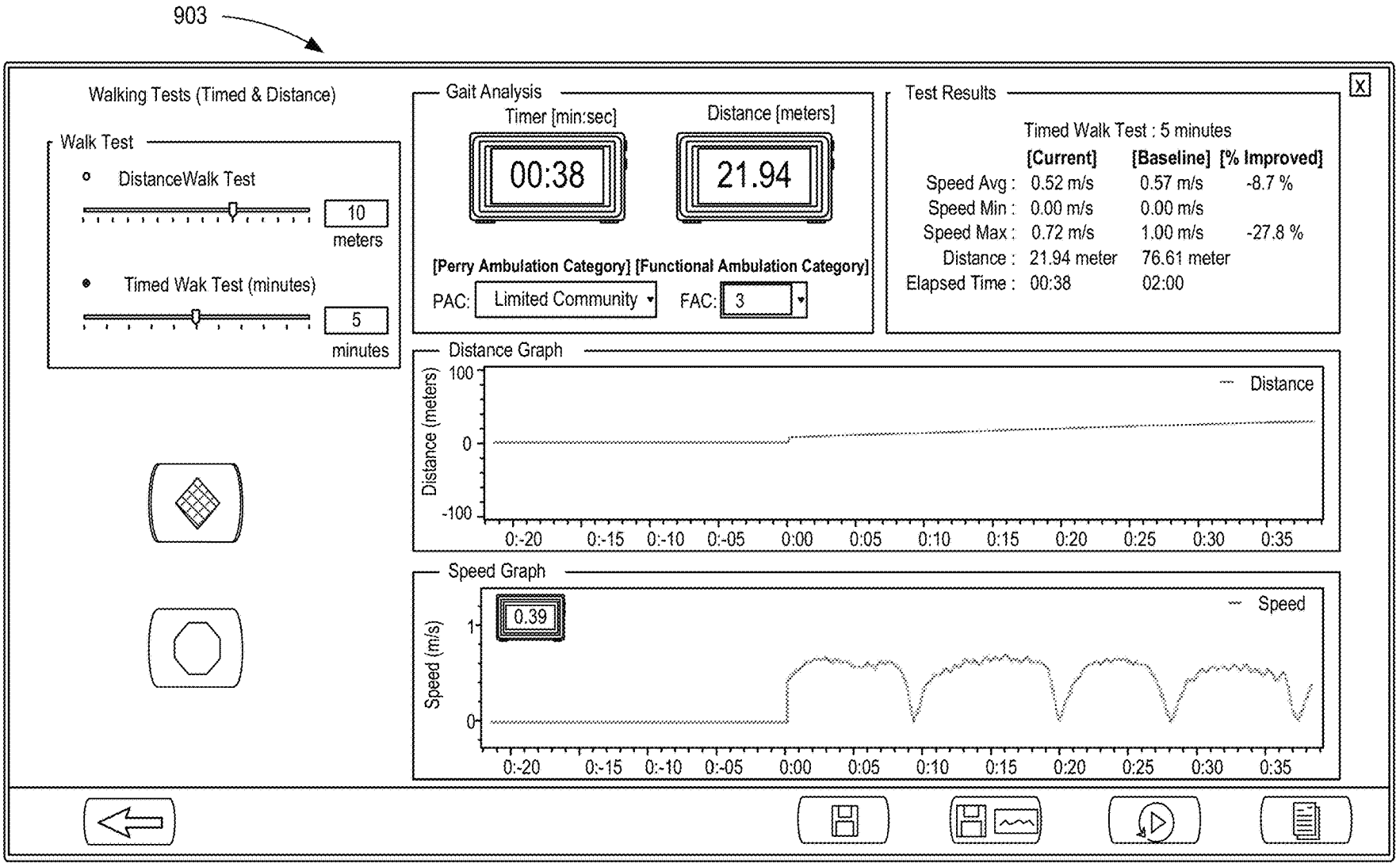

903
Walking Tests (Timed & Distance)
Walk Test
DistanceWalk Test
10
meters
Timed Wak Test (minutes)
5
minutes
Gait Analysis
Timer [min:sec]
00:38
Distance [meters]
21.94
[Perry Ambulation Category] [Functional Ambulation Category]
PAC: Limited Community
FAC: 3
Test Results
Timed Walk Test : 5 minutes
[Current] [Baseline] [% Improved]
Speed Avg : 0.52 m/s 0.57 m/s -8.7 %
Speed Min : 0.00 m/s 0.00 m/s
Speed Max : 0.72 m/s 1.00 m/s -27.8 %
Distance : 21.94 meter 76.61 meter
Elapsed Time : 00:38 02:00
Distance Graph
Distance (meters)
100
0
-100
Distance
0:-20 0:-15 0:-10 0:-05 0:00 0:05 0:10 0:15 0:20 0:25 0:30 0:35
Speed Graph
Speed (m/s)
0.39
1
0
Speed
0:-20 0:-15 0:-10 0:-05 0:00 0:05 0:10 0:15 0:20 0:25 0:30 0:35

FIG. 58

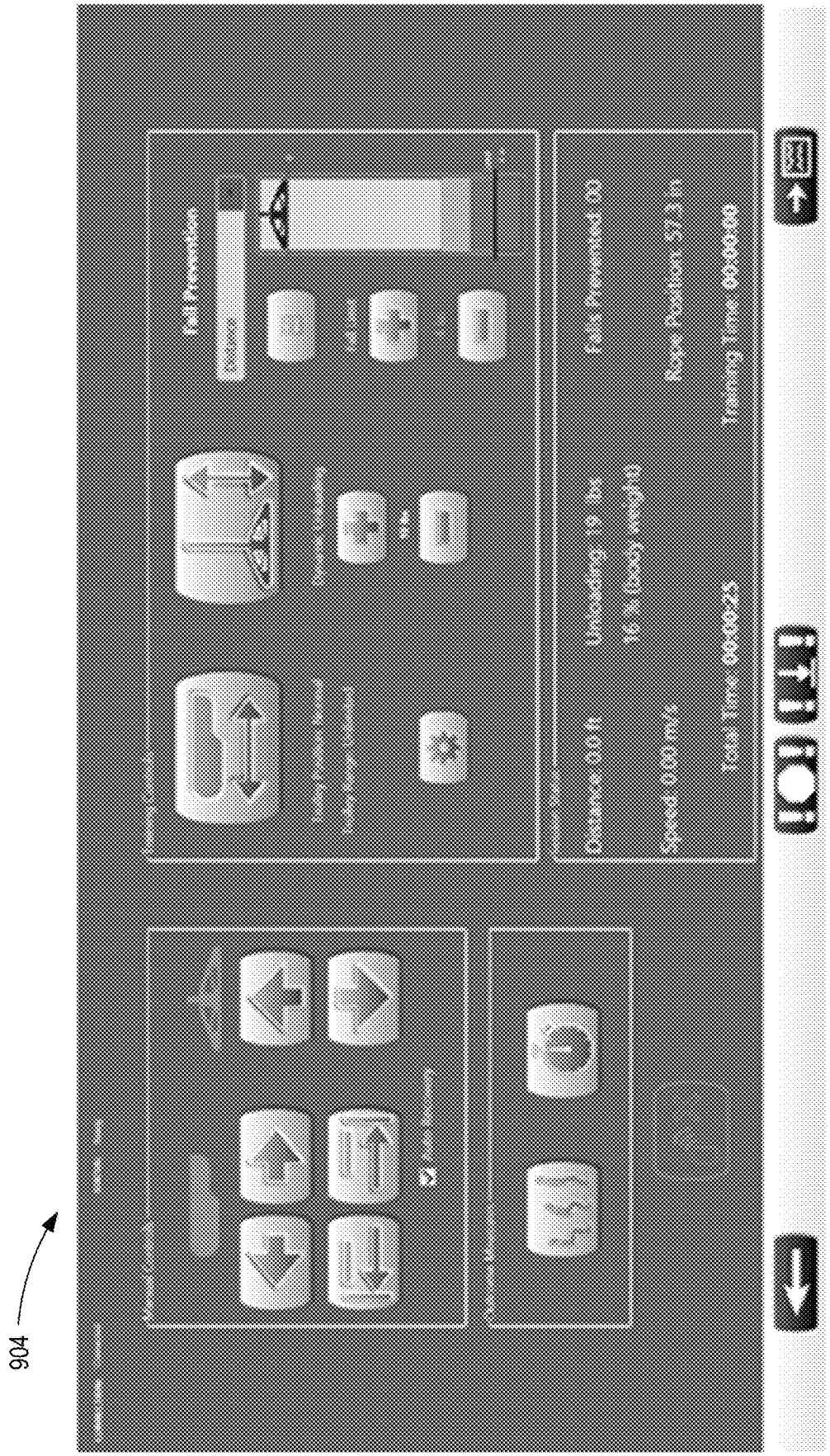


FIG. 59

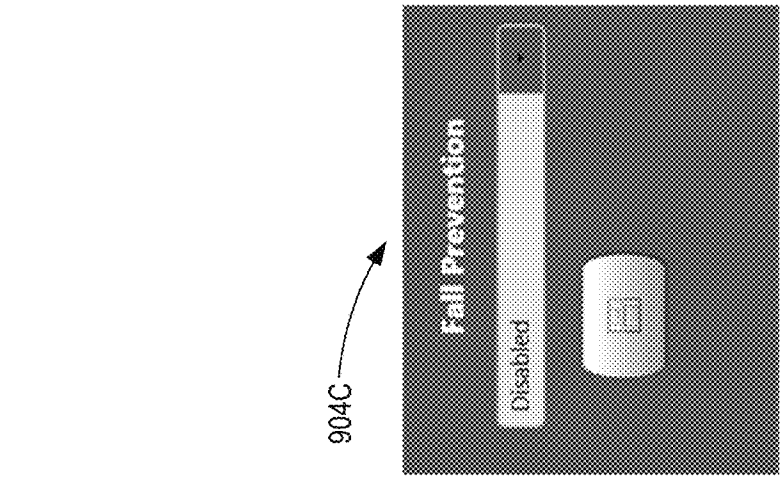


FIG. 62

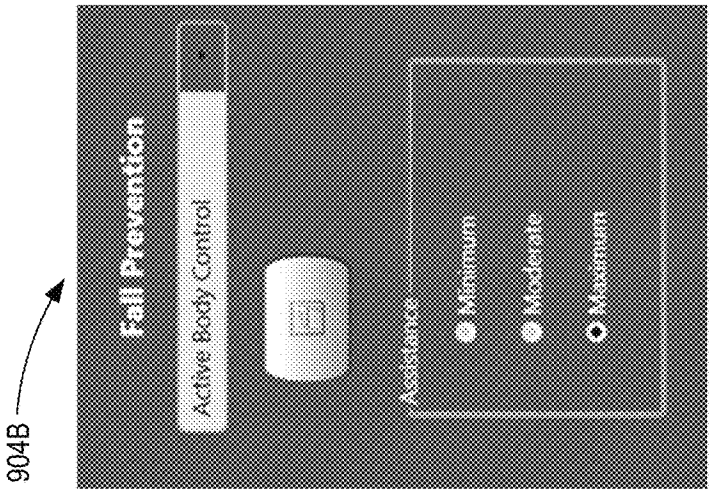


FIG. 61

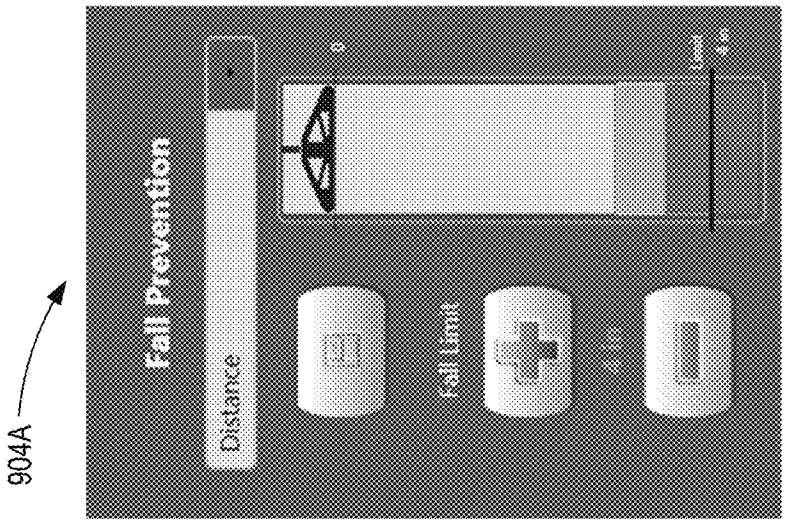


FIG. 60

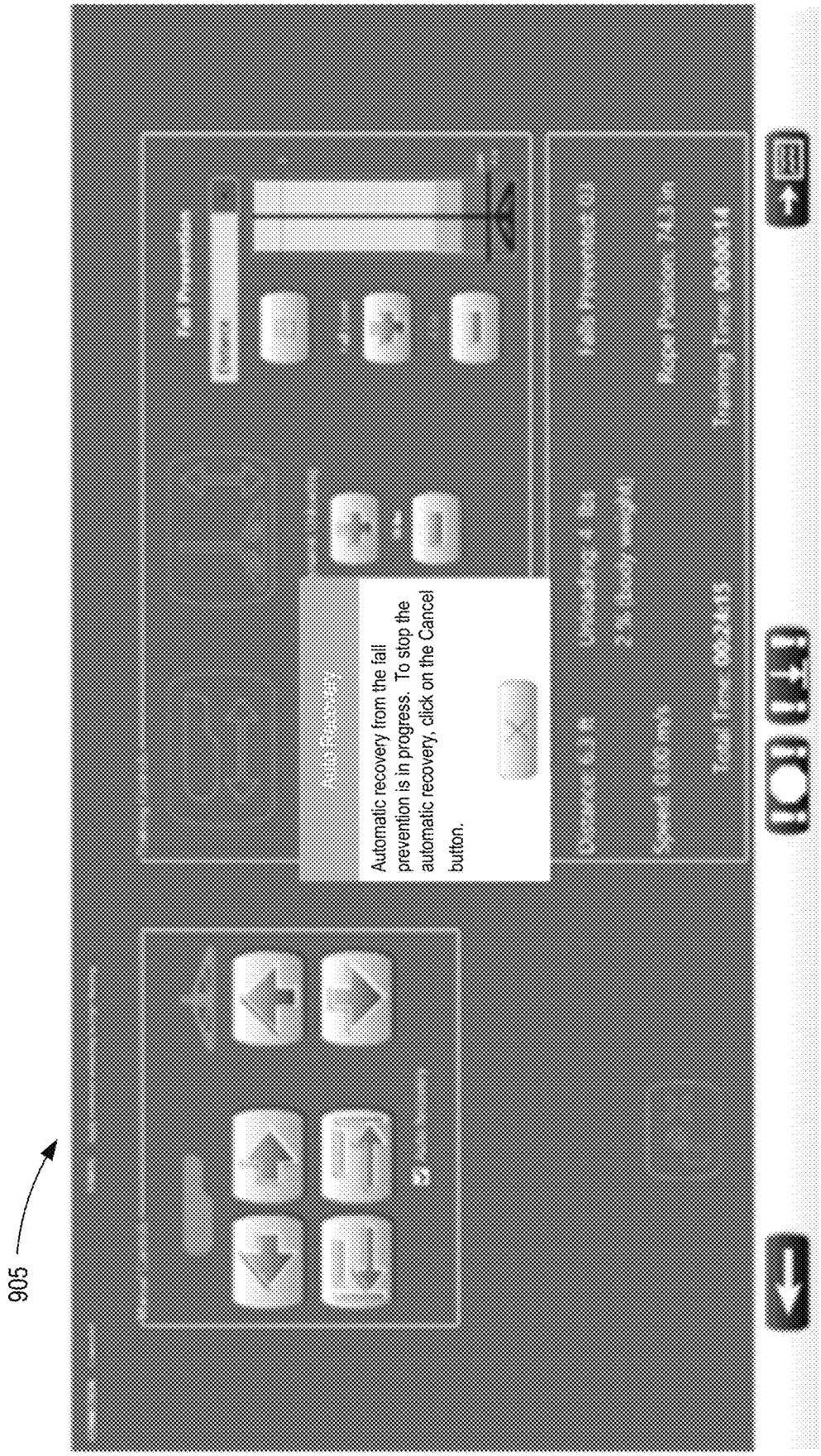

905
Automatic recovery from the fail prevention is in progress. To stop the automatic recovery, click on the Cancel button.

FIG. 63

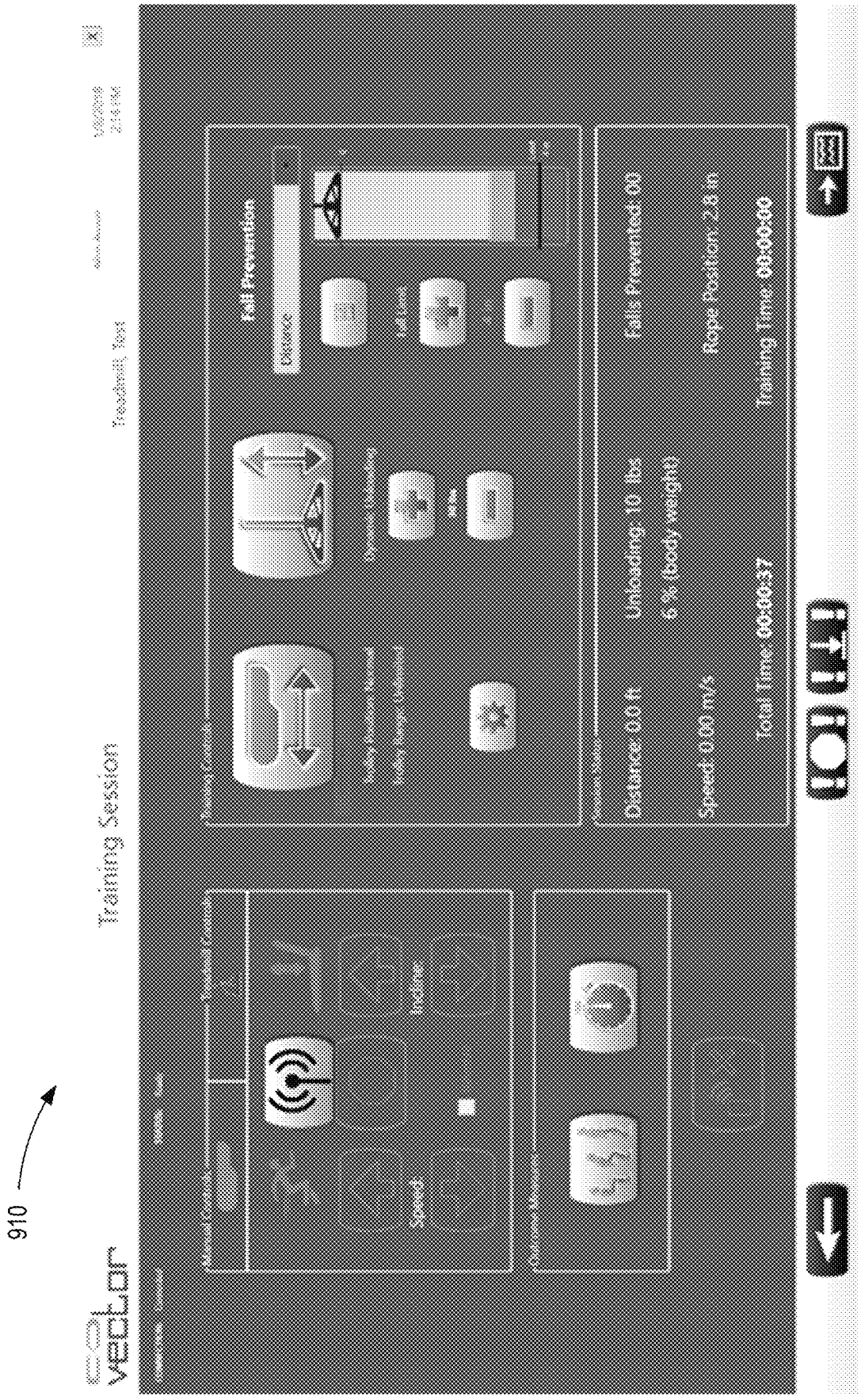

910
Training Session
Fall Prevention
Distance
Unloading: 10 lbs
6 % (body weight)
Falls Prevention: 00
Rope Position: 2.0 in
Training Time: 00:00:00
Distance: 0.0 ft
Speed: 0.00 m/s
Total Time: 00:00:37

FIG. 64

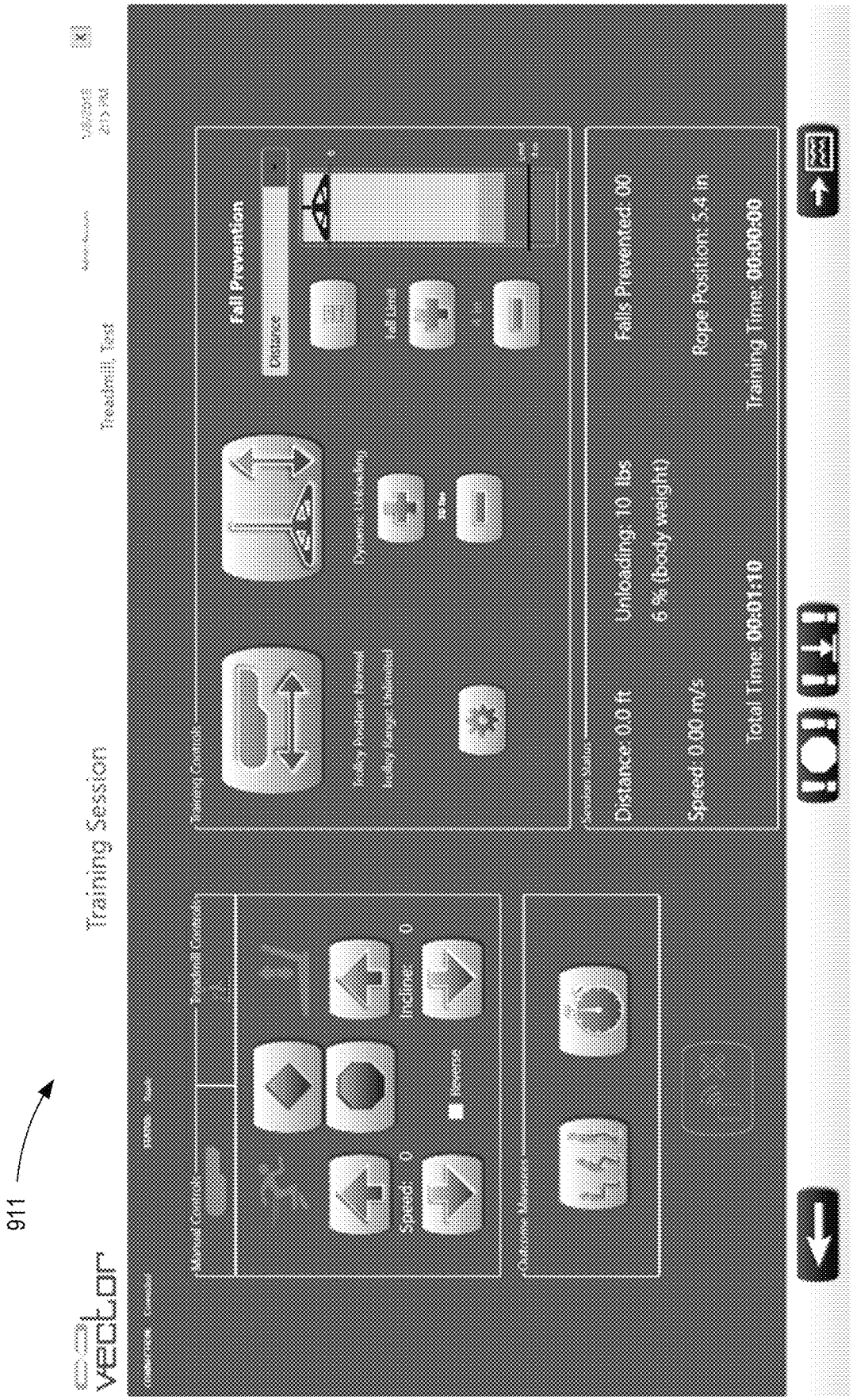

911
Training Session
Treadmill Test
Fall Prevention
Distance
Distance: 0.0 ft
Unloading: 10 lbs
6 % (body weight)
Speed: 0.00 m/s
Falls Prevented: 00
Rope Position: 5.4 in
Total Time: 00:01:10
Training Time: 00:00:00

FIG. 65

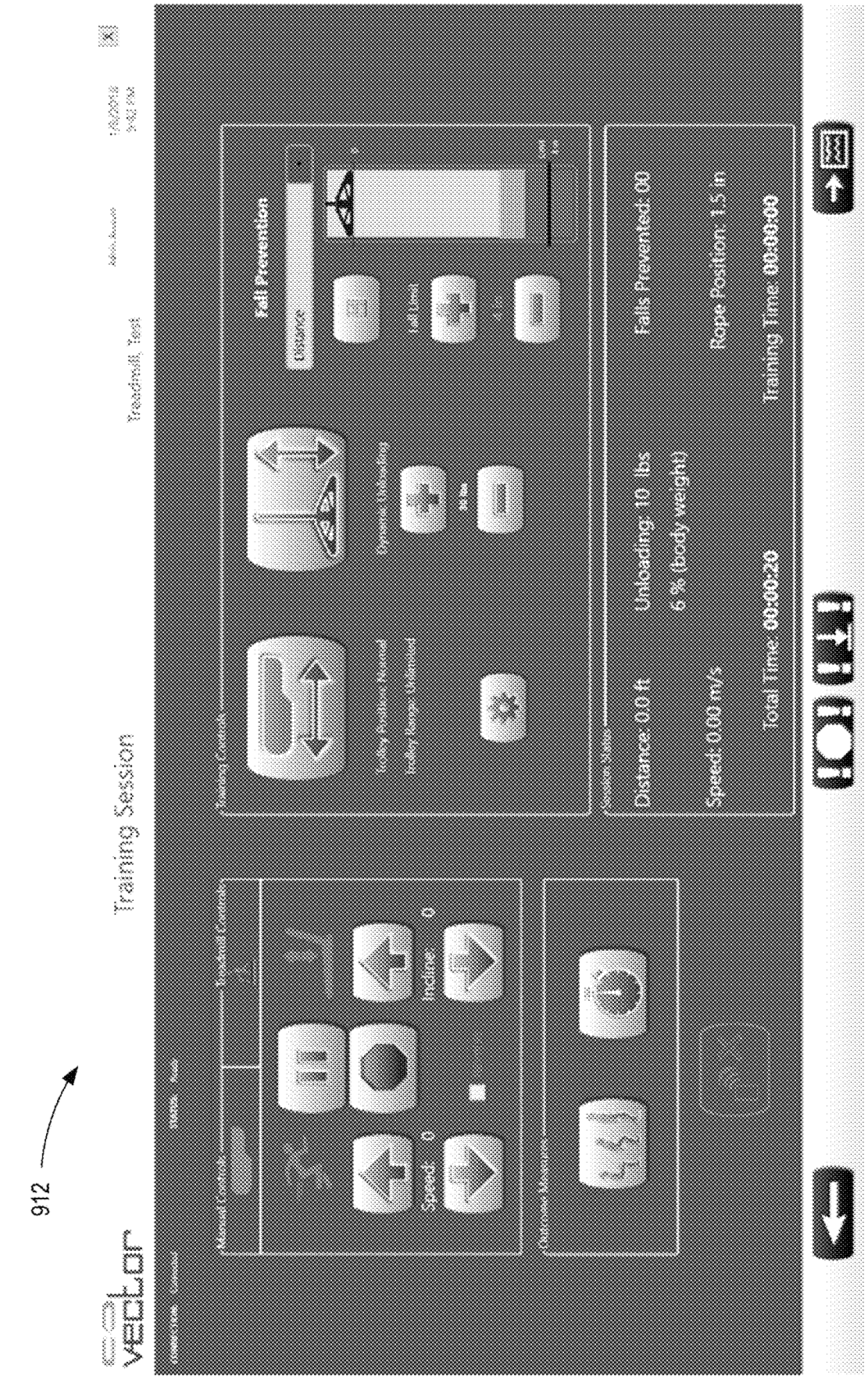

912
Training Session
Fall Prevention
Distance
Unloading: 10 lbs
6.3% (body weight)
Falls Prevented: 08
Rope Position: 1.5 in
Distance: 0.0 ft
Speed: 0.00 m/s
Total Time: 00:00:20
Training Time: 00:00:20

FIG. 66

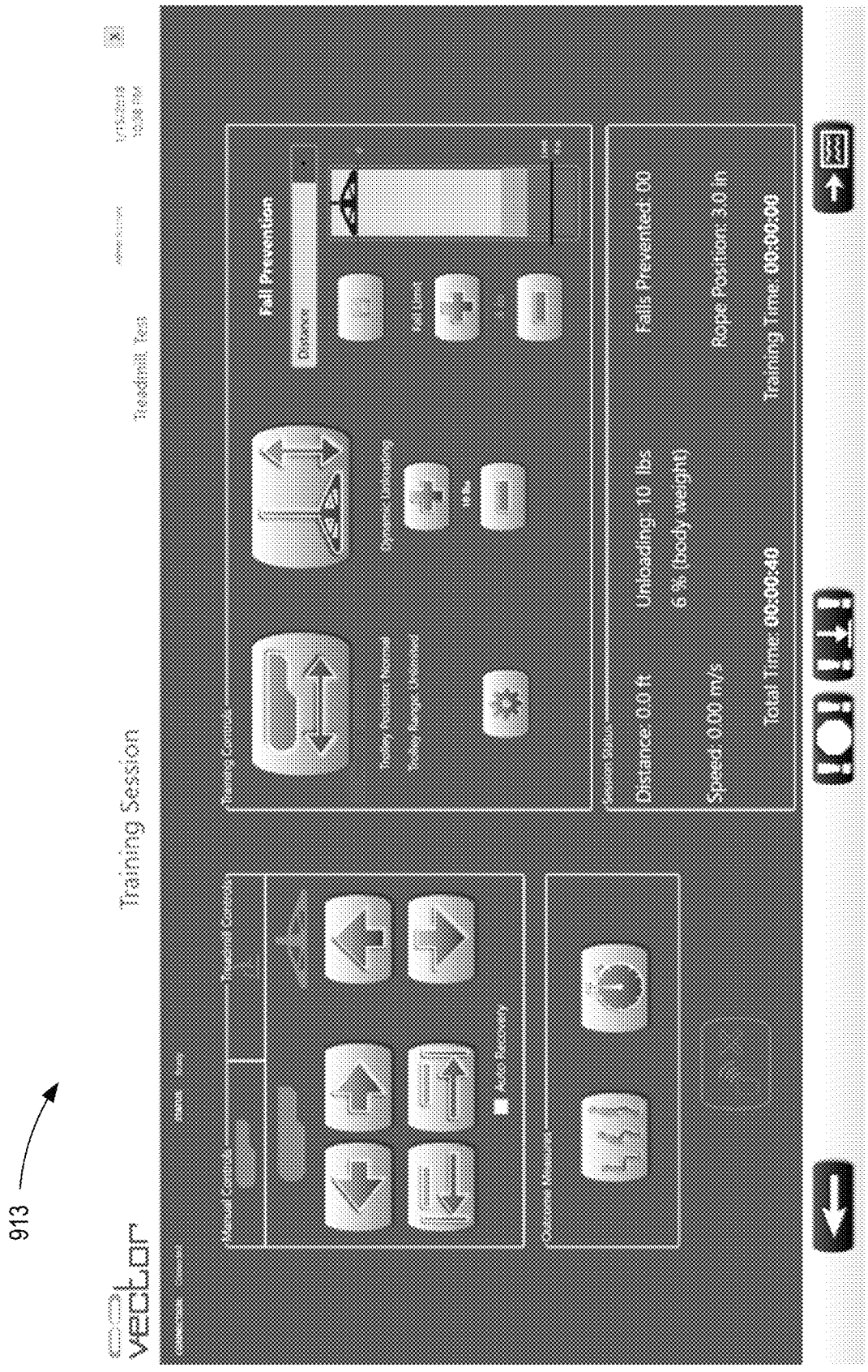

913
vector
Training Session
Treadmill Test
Fall Prevention
Distance
Safety
Fall Alarm
Fall Prevention
Safety
Unloading: 10 lbs
(Body Weight)
Distance: 0.0 ft
Speed: 0.00 m/s
Falls Prevented: 00
Rope Position: 3.0 in
Total Time: 00:00:00
Training Time: 00:00:00

FIG. 67

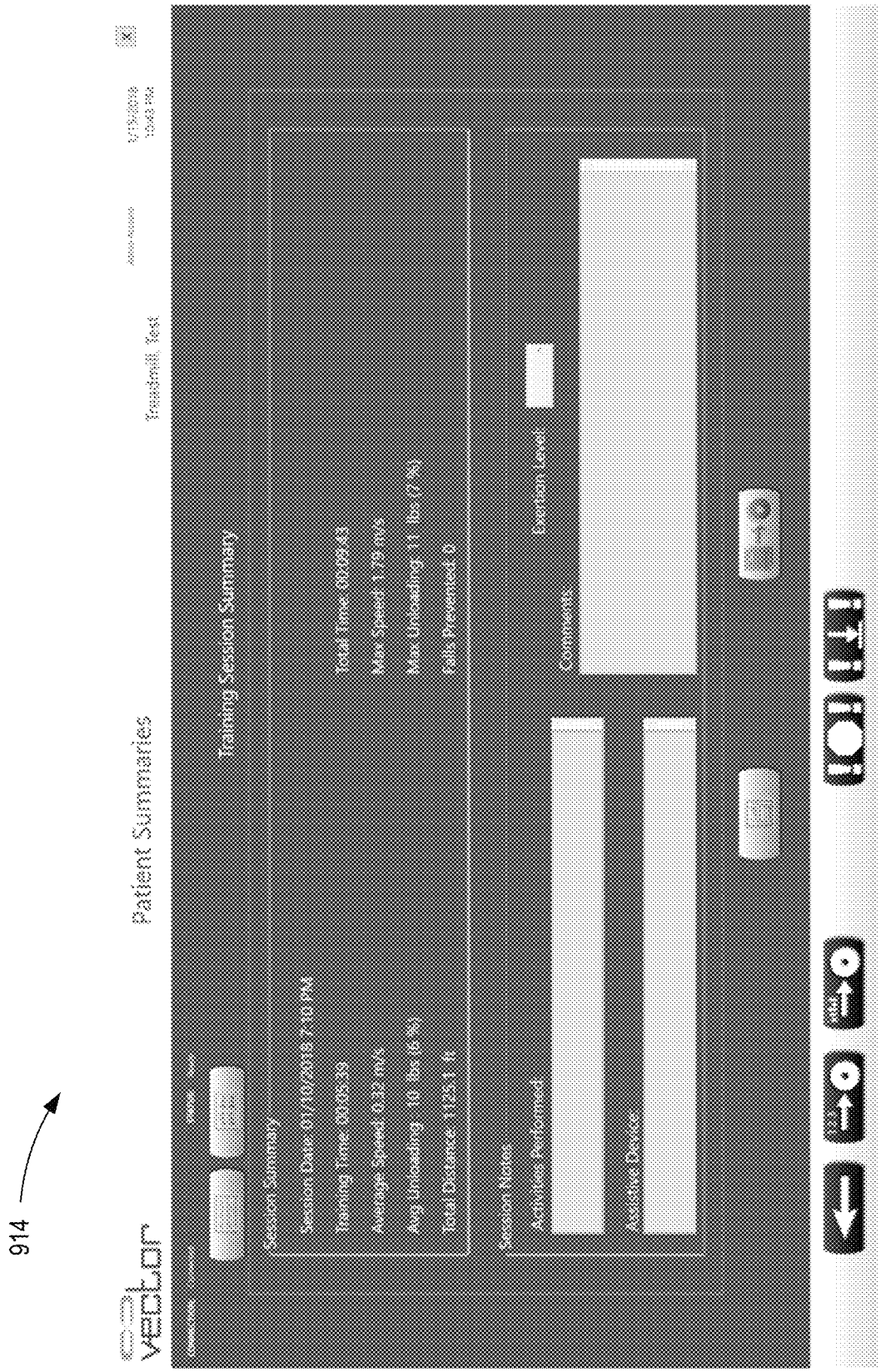

914
vector
Patient Summaries
Treadmill Test
Training Session Summary
Session Summary
Session Date: 01/10/2018 7:01 PM
Training Time: 00:05:33
Average Speed: 0.32 mph
Avg Unloading: 10 lbs (0 %)
Total Distance: 112.1 ft
Total Time: 00:05:33
Max Speed: 1.75 mph
Max Unloading: 11 lbs (7 %)
Falls Prevented: 0
Session Notes
Ambulation Balanced
Ambulation Distance
Comments
Exercise Level

FIG. 68

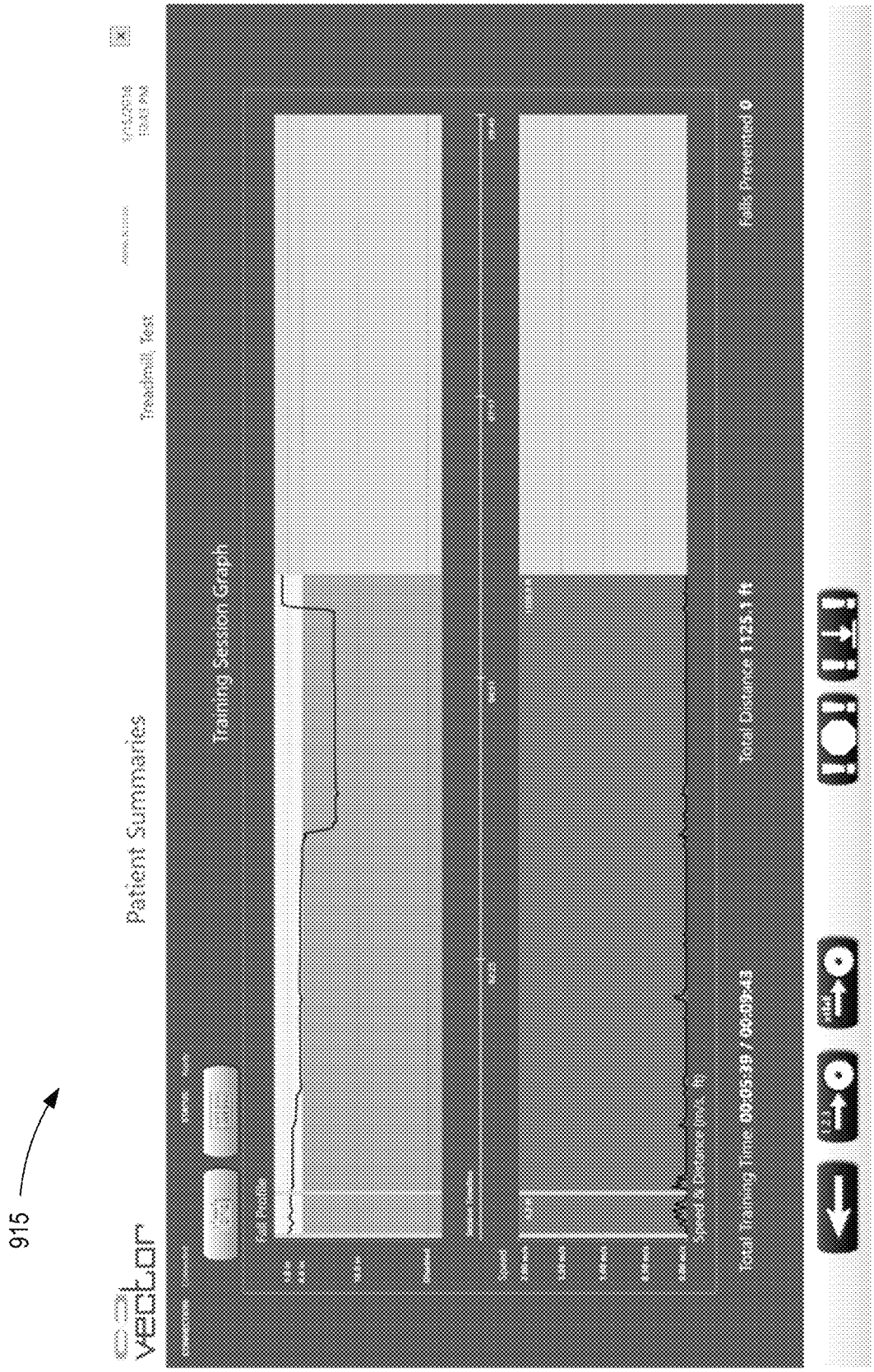

915
Patient Summaries
Training Session Graph
Treadmill Test

FIG. 69

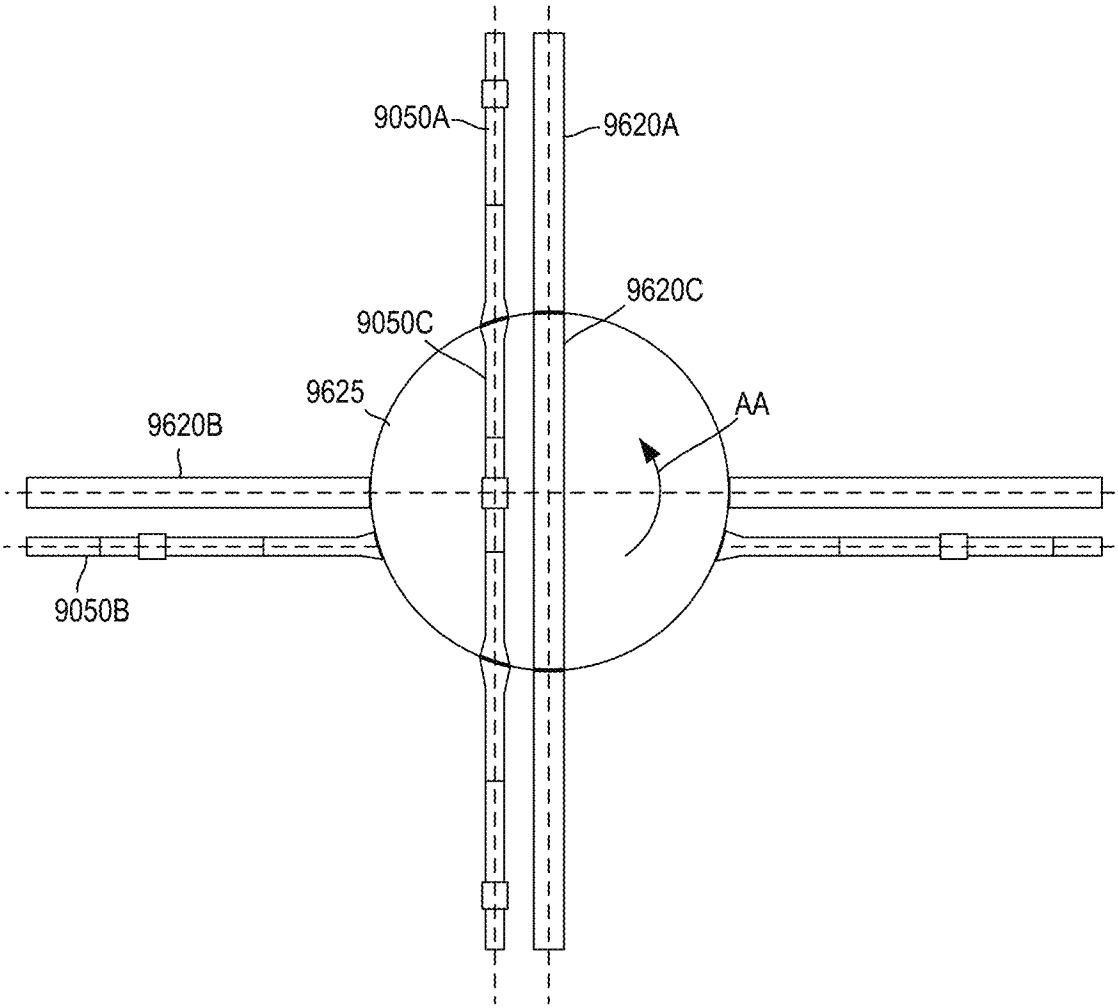


FIG. 70

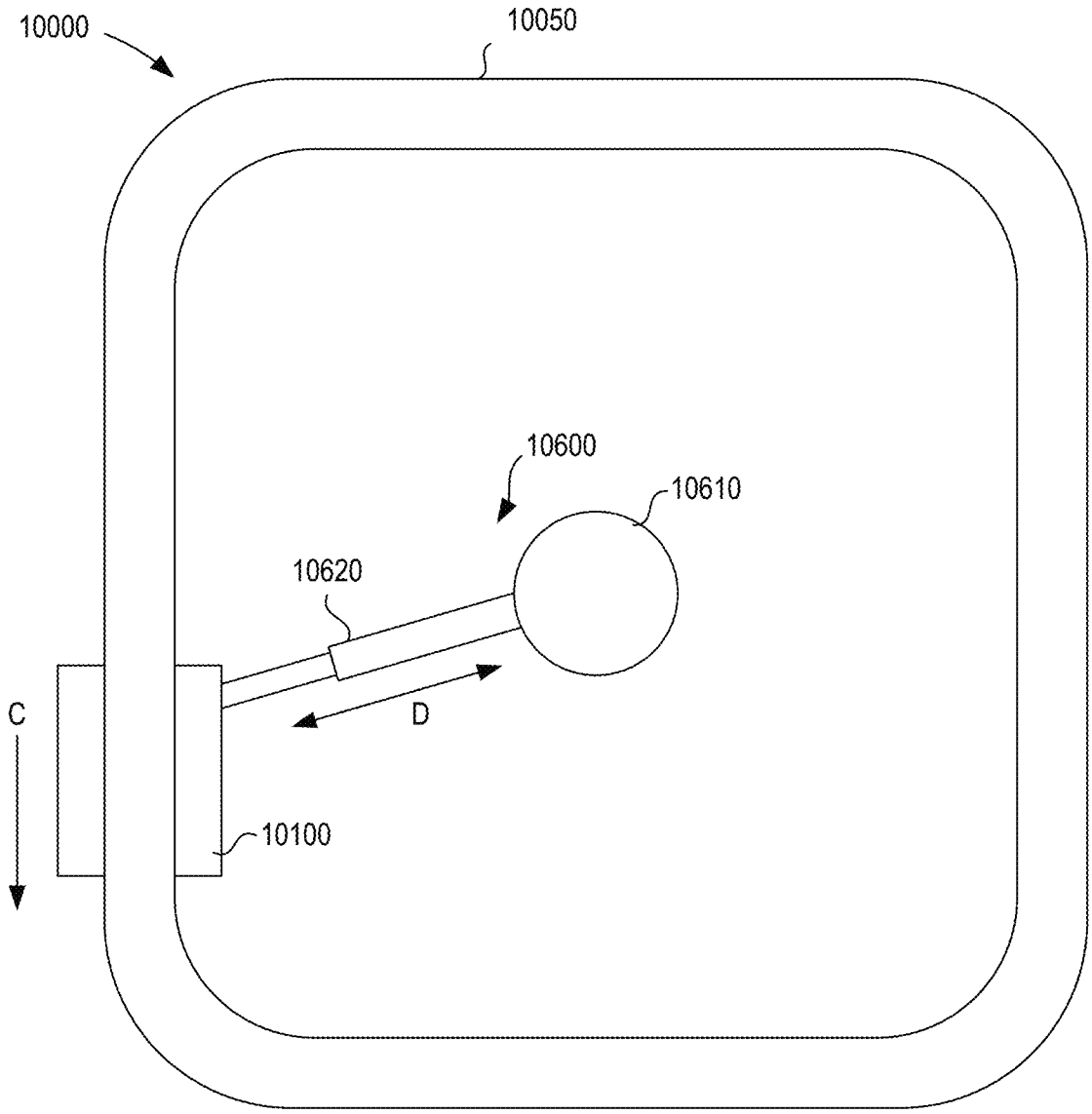


FIG. 71

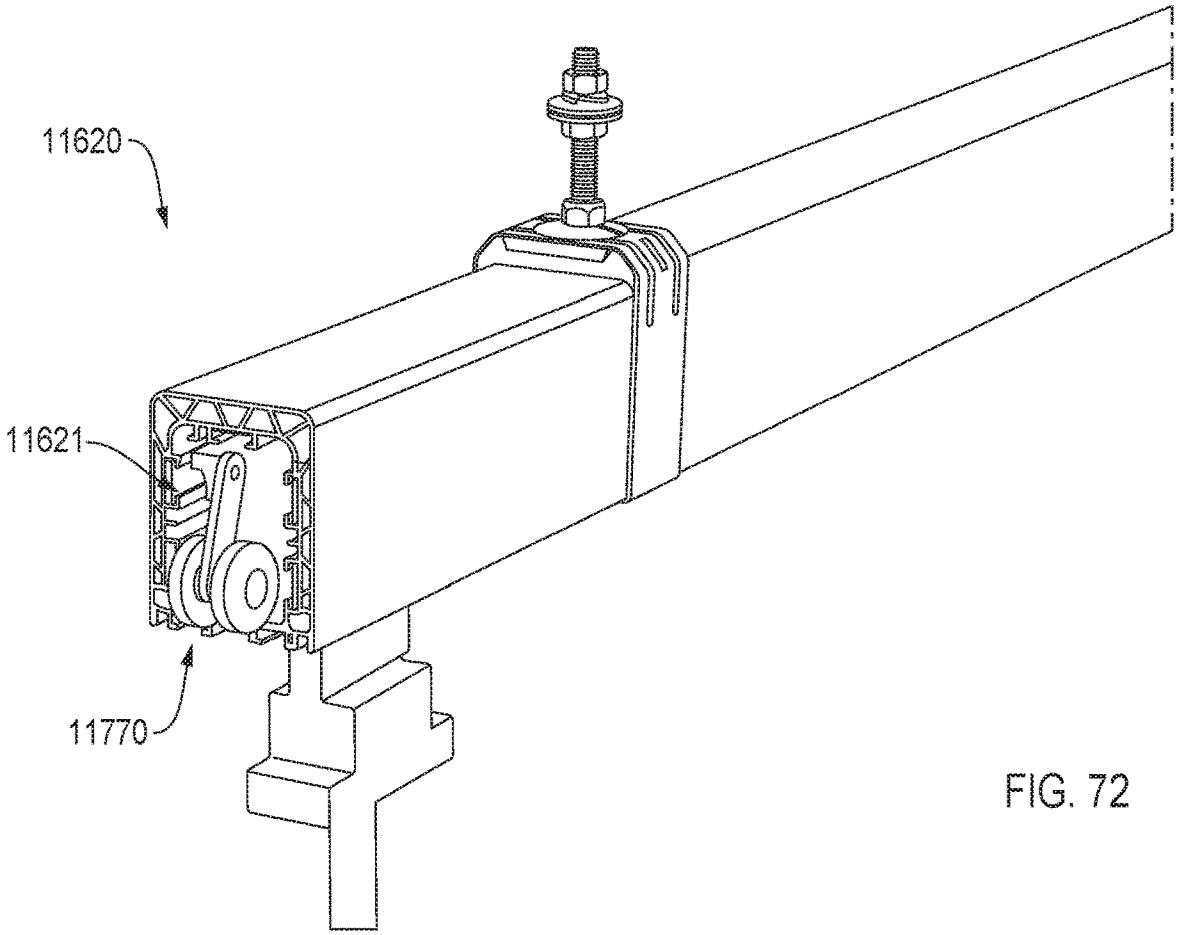


FIG. 72

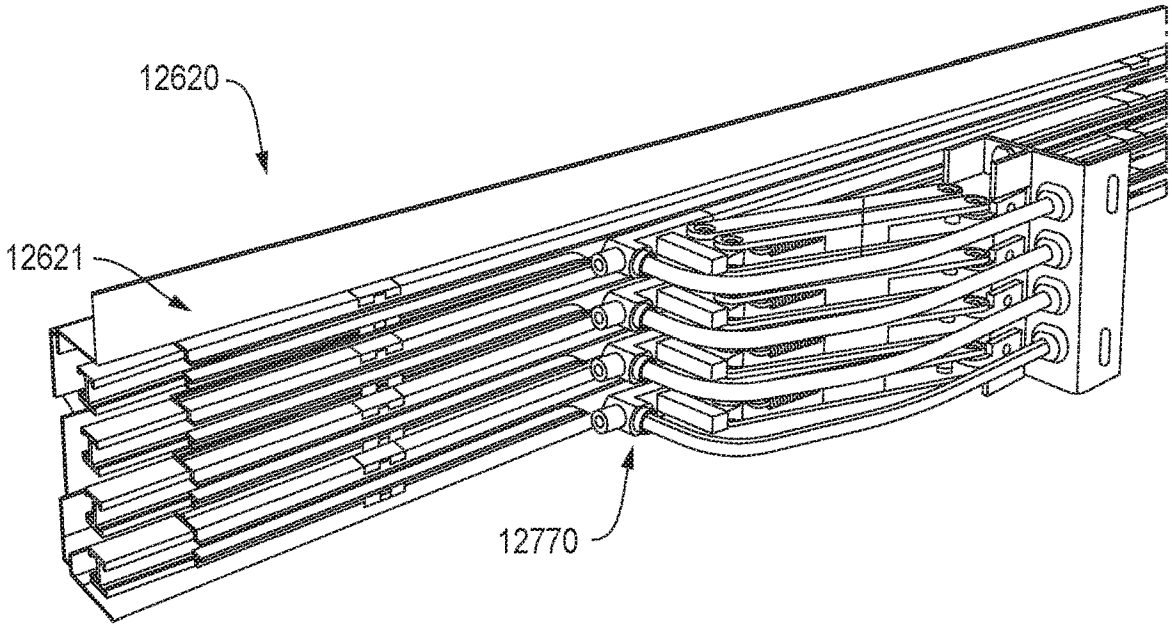


FIG. 73

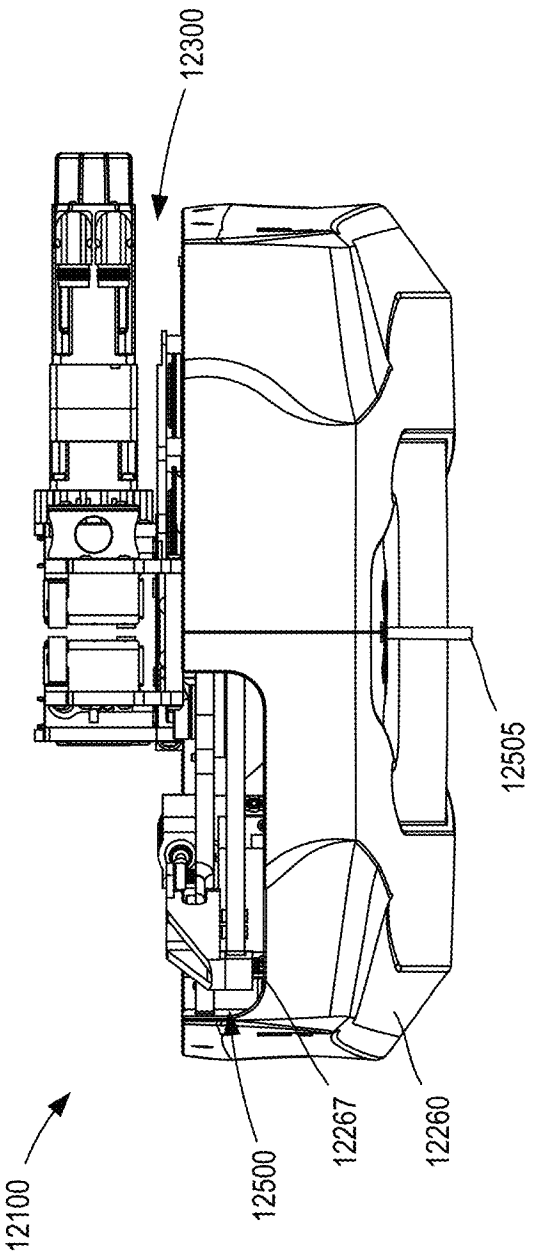

12300
12505
12100
12500
12267
12260

FIG. 74

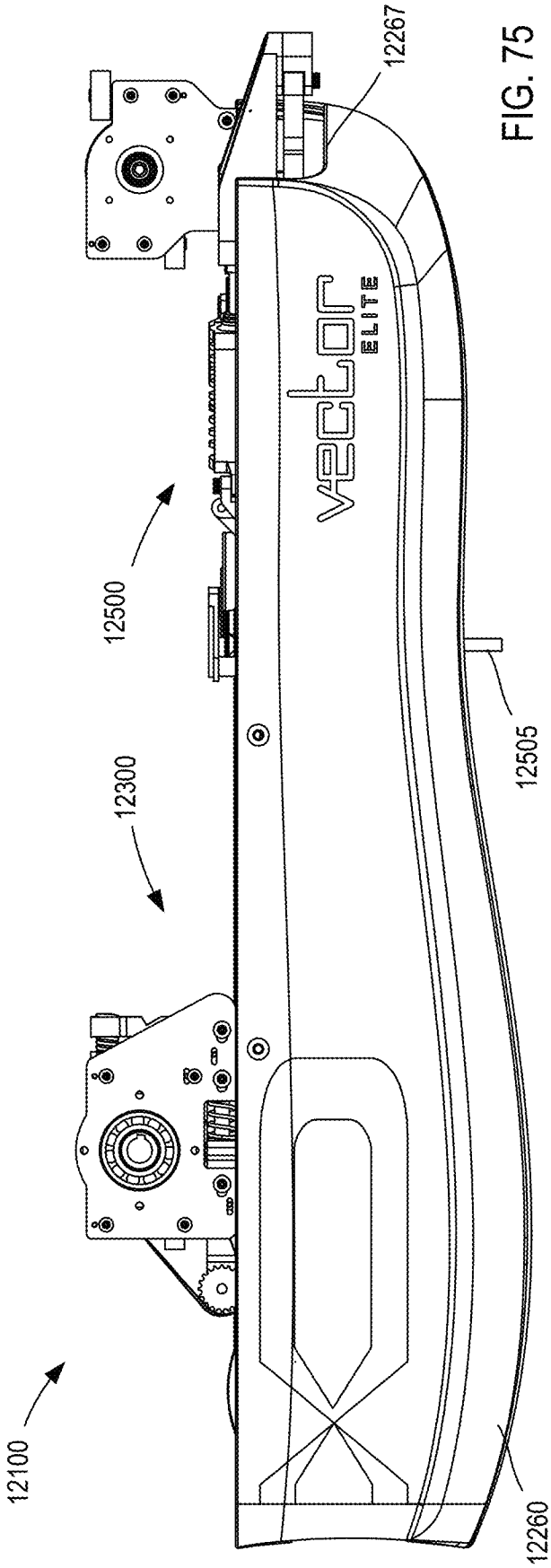

12267
vector
ELITE
12500
12505
12300
12100
12260

FIG. 75

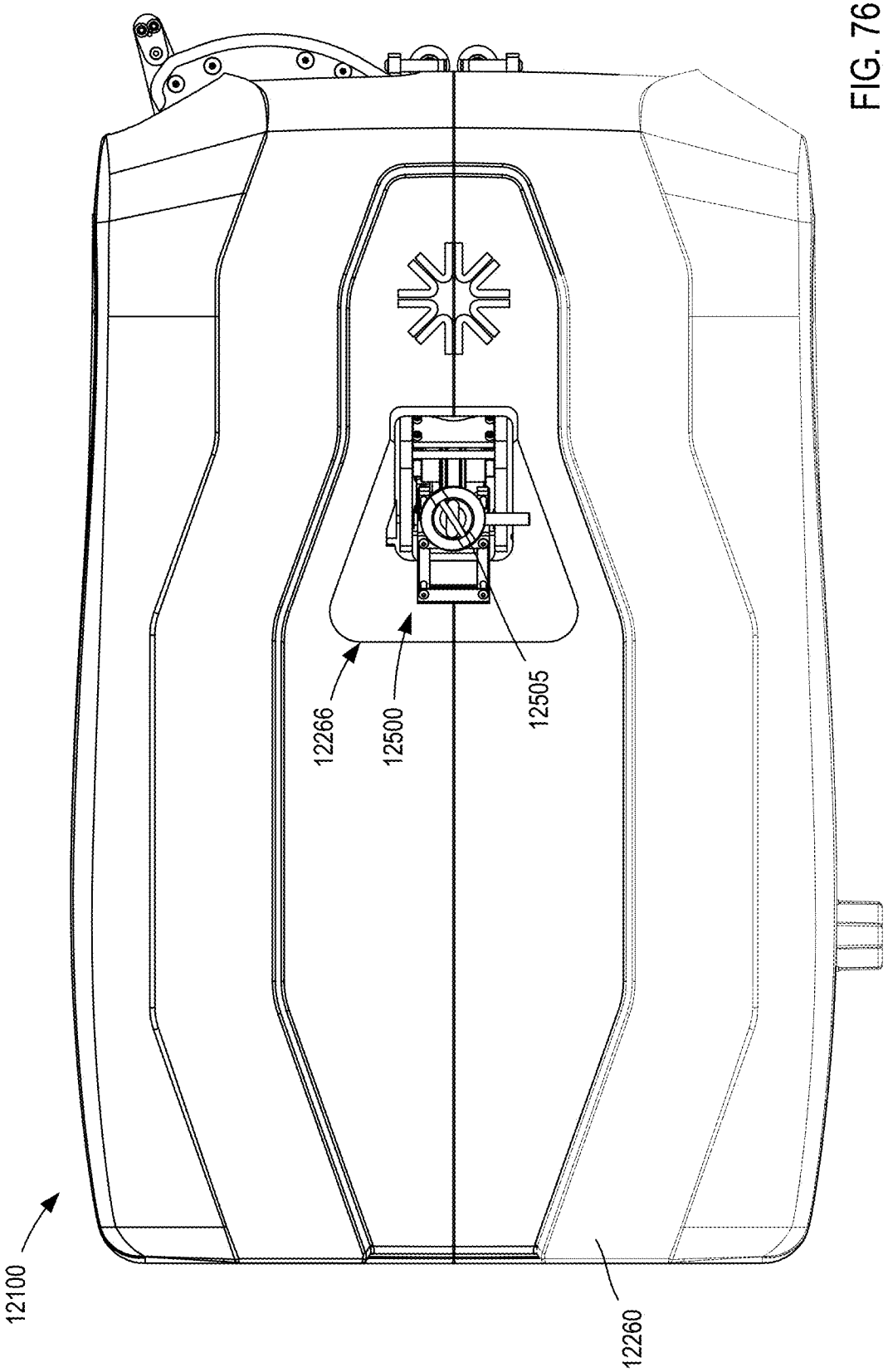


FIG. 76

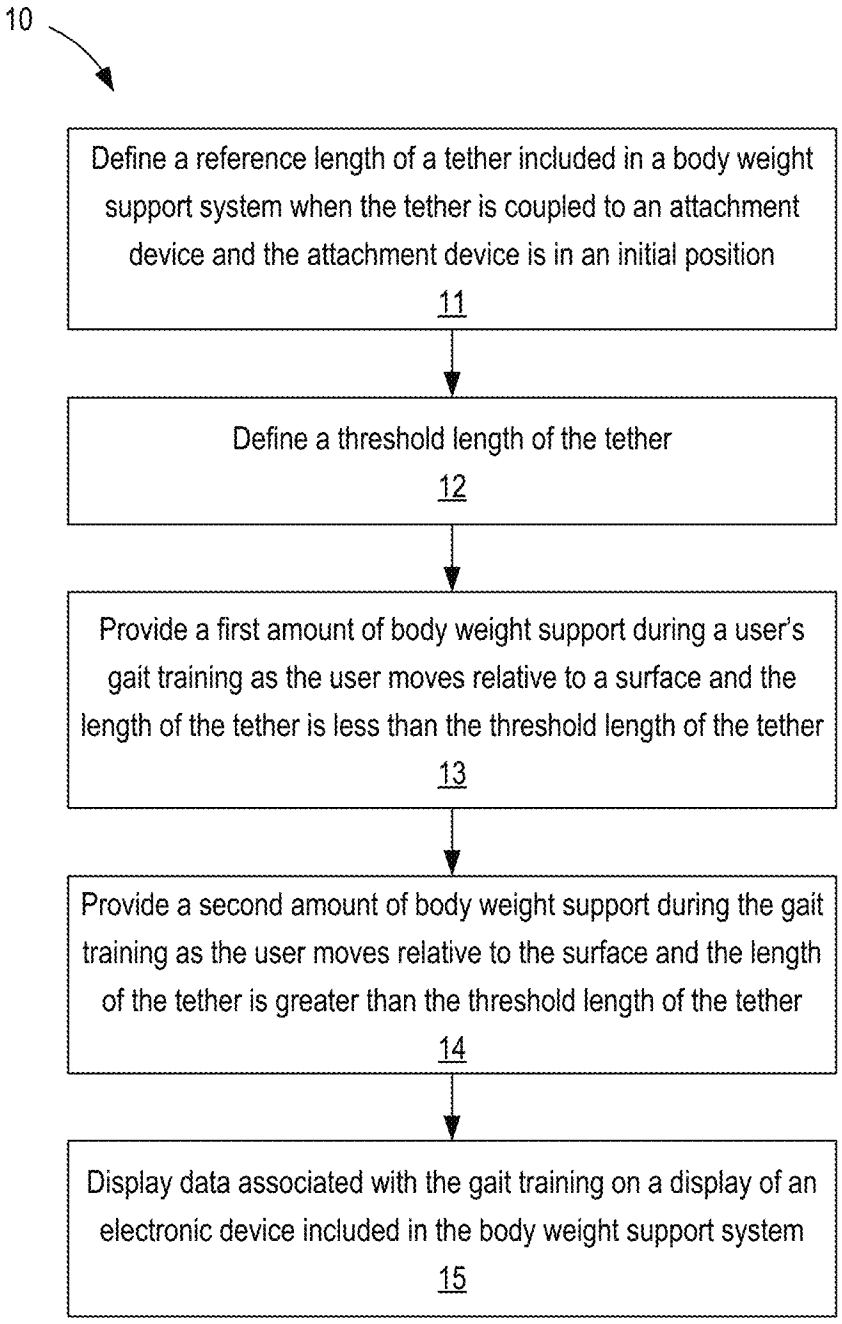

10
Define a reference length of a tether included in a body weight support system when the tether is coupled to an attachment device and the attachment device is in an initial position
11
Define a threshold length of the tether
12
Provide a first amount of body weight support during a user's gait training as the user moves relative to a surface and the length of the tether is less than the threshold length of the tether
13
Provide a second amount of body weight support during the gait training as the user moves relative to the surface and the length of the tether is greater than the threshold length of the tether
14
Display data associated with the gait training on a display of an electronic device included in the body weight support system
15

FIG. 77

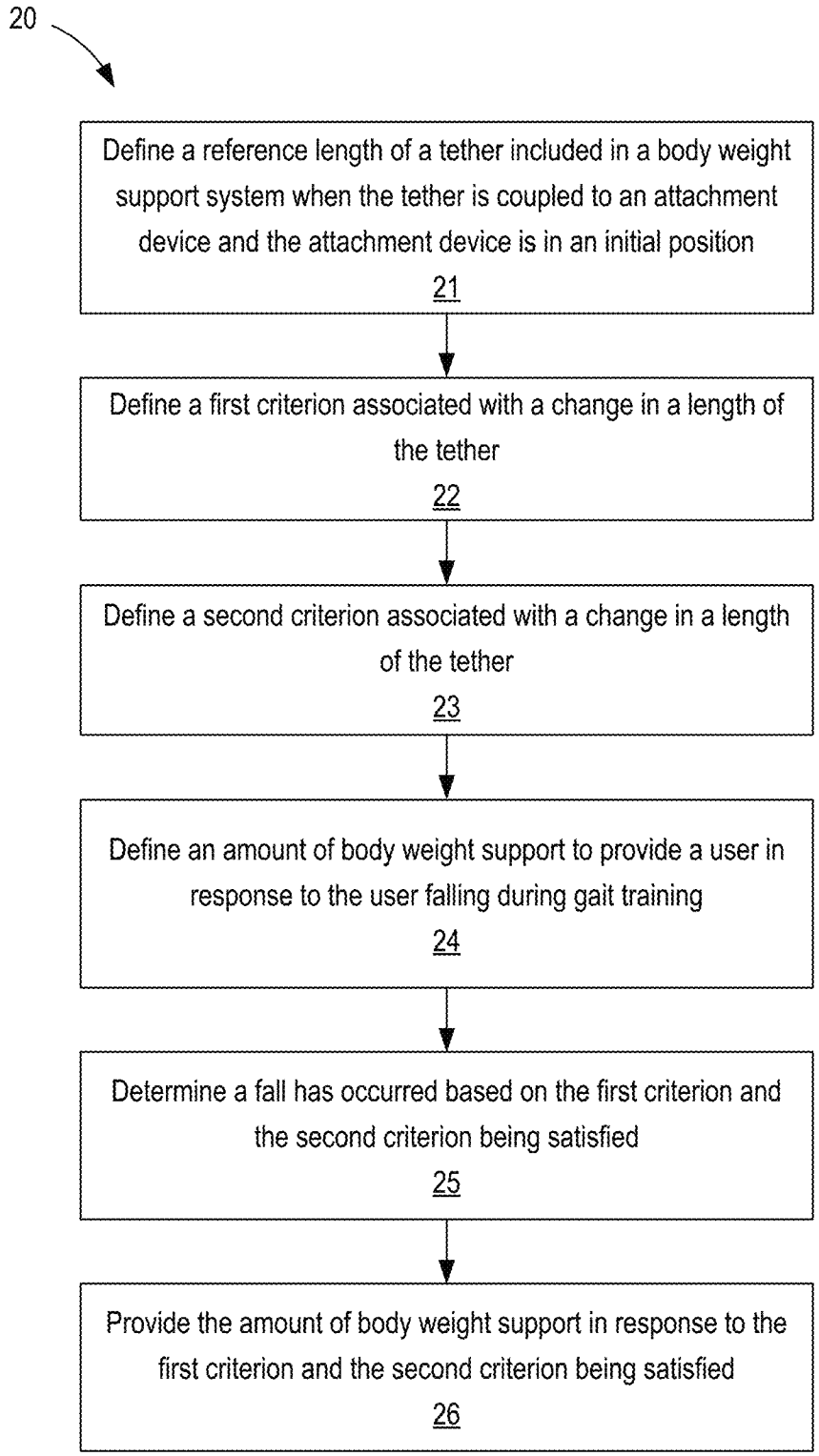

20
Define a reference length of a tether included in a body weight support system when the tether is coupled to an attachment device and the attachment device is in an initial position
21
Define a first criterion associated with a change in a length of the tether
22
Define a second criterion associated with a change in a length of the tether
23
Define an amount of body weight support to provide a user in response to the user falling during gait training
24
Determine a fall has occurred based on the first criterion and the second criterion being satisfied
25
Provide the amount of body weight support in response to the first criterion and the second criterion being satisfied
26

FIG. 78

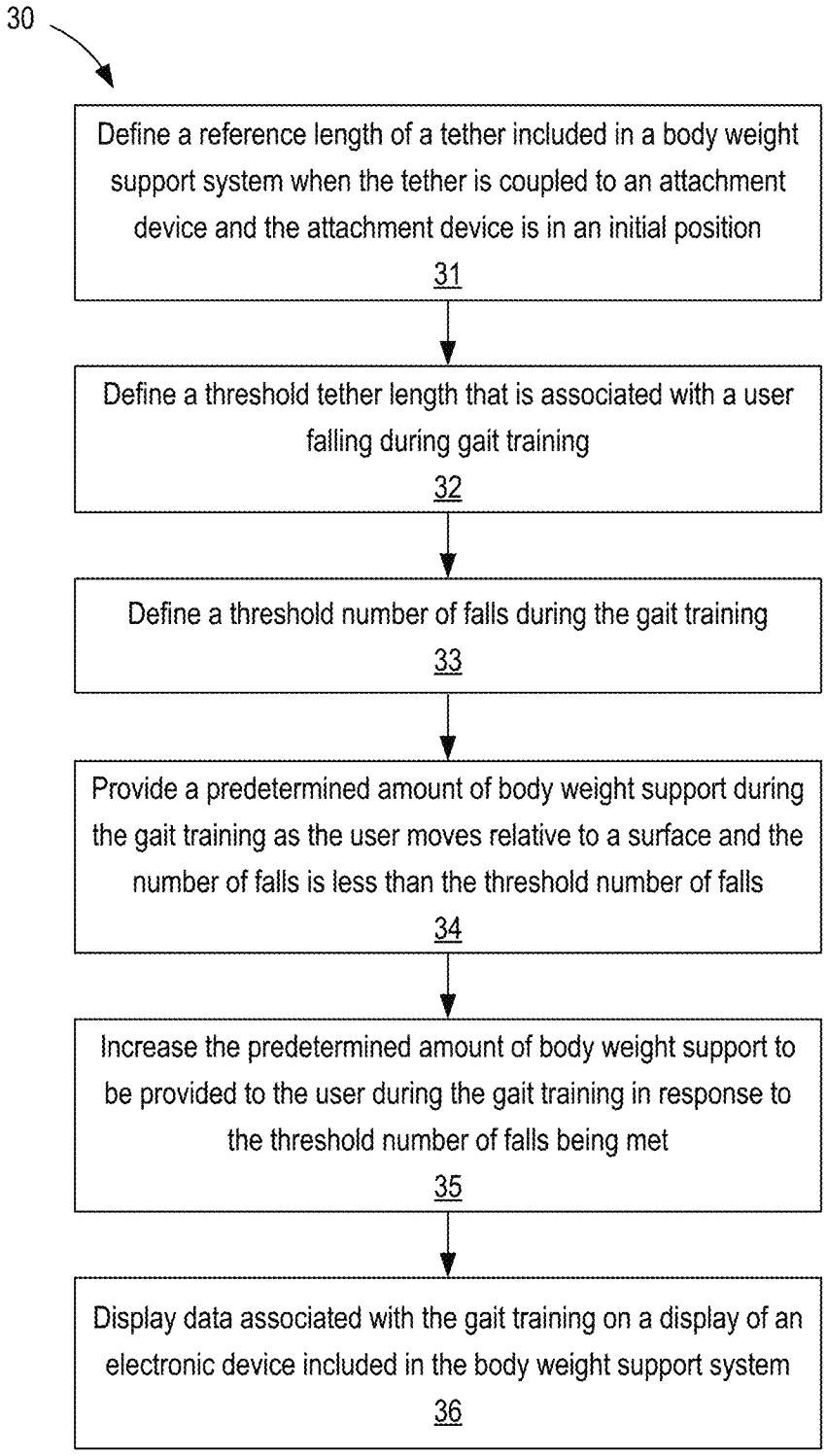

30
Define a reference length of a tether included in a body weight support system when the tether is coupled to an attachment device and the attachment device is in an initial position
31
Define a threshold tether length that is associated with a user falling during gait training
32
Define a threshold number of falls during the gait training
33
Provide a predetermined amount of body weight support during the gait training as the user moves relative to a surface and the number of falls is less than the threshold number of falls
34
Increase the predetermined amount of body weight support to be provided to the user during the gait training in response to the threshold number of falls being met
35
Display data associated with the gait training on a display of an electronic device included in the body weight support system
36

FIG. 79

METHODS AND APPARATUS FOR BODY WEIGHT SUPPORT SYSTEM

CROSS-REFERENCE TO RELATED APPLICATIONS

This application claims priority to and the benefit of U.S. Provisional Patent Application No. 62/458,648 entitled, "Methods and Apparatus for Body Weight Support System," filed Feb. 14, 2017, the disclosure of which is incorporated herein by reference in its entirety.

This application is related to U.S. Patent Publication No. 2015/0143627 entitled, "Methods and Apparatus for Body Weight Support System," filed Feb. 3, 2015, which is a continuation-in-part of U.S. Pat. No. 9,855,177 entitled, "Methods and Apparatus for Body Weight Support System," filed Mar. 26, 2014, which is a continuation-in-part of U.S. Pat. No. 9,682,000 entitled, "Methods and Apparatus for Body Weight Support System," filed Jan. 20, 2013, the disclosure of each of which is incorporated herein by reference in its entirety.

BACKGROUND

The embodiments described herein relate to apparatus and methods for supporting the body weight of a user. More particularly, the embodiments described herein relate to apparatus and methods for supporting the body weight of a user during gait therapy.

Successfully delivering intensive yet safe gait therapy to individuals with significant walking deficits can present challenges to skilled therapists. In the acute stages of many neurological injuries such as stroke, spinal cord injury, traumatic brain injury, or the like individuals often exhibit highly unstable walking patterns and poor endurance, making it difficult to safely practice gait for both the user (e.g., patient) and therapist. Because of this, rehabilitation centers often move over-ground gait training to a treadmill where body-weight support systems can help minimize falls while raising the intensity of the training.

In some instances, body-weight supported treadmill training can promote gains in walking ability similar to or greater than conventional gait training. Unfortunately, there are few systems for transitioning patients from training on a treadmill to safe, weight-supported over-ground gait training. Furthermore, since a primary goal of most individuals with walking impairments is to walk in their homes and in their communities rather than on a treadmill, it is often desirable that therapeutic interventions targeting gait involve over-ground gait training (e.g., not on a treadmill).

Some known support systems involve training individuals with gait impairments over smooth, flat surfaces. In some systems, however, therapists may be significantly obstructed from interacting with the patient, particularly the lower legs of the patient. For patients that require partial assistance to stabilize their knees and/or hips or that need help to propel their legs, the systems present significant barriers between the patient and the therapist.

Some known gait support systems are configured to provide static unloading to a patient supported by the system. That is, under static unloading, the length of shoulder straps that support the patient are set to a fixed length such that the patient either bears substantially all of their weight when the straps are slack or substantially no weight when the straps are taught. Static unloading systems have been shown to result in abnormal ground reaction forces and altered muscle activation patterns in the lower extremities.

In addition, static unloading systems may limit the vertical excursions of a patient that prevent certain forms of balance and postural therapy where a large range of motion is necessary. As a result, some known systems may not be able to raise a patient from a wheelchair to a standing position, thereby restricting the use of the system to individuals who are not relegated to a wheelchair (e.g., those patients with minor to moderate gait impairments).

In some known static support systems, there may be a limitation on the amount of body-weight support. In such a system, the body-weight support cannot be modulated continuously, but rather is adjusted before the training session begins and remains substantially fixed at that level during training. Furthermore, the amount of unloading cannot be adjusted continuously since it requires the operator to manually adjust the system.

In other known systems, a patient may be supported by a passive trolley and rail system configured to support the patient while the patient physically drags the trolley along the overhead rail during gait therapy. While the trolley may have a relatively small mass, the patient may feel the presence of the mass. Accordingly, rather than being able to focus on balance, posture, and walking ability, the patient may have to compensate for the dynamics of the trolley. For example, on a smooth flat surface, if the subject stops abruptly, the trolley may continue to move forward and potentially destabilize the subject, thereby resulting in an abnormal compensatory gait strategy that could persist when the subject is removed from the device.

Some known over-ground gait support systems include a motorized trolley and rail system. In such known systems, the motorized trolley can be relatively bulky, thereby placing height restrictions on system. For example, in some known systems, there may be a maximum suitable height for effective support of a patient. In some known systems, a minimum ceiling height may be needed for the system to provide support for patients of varying height.

While the trolley is motorized and programmed to follow the subject's movement, the mechanics and overall system dynamics can result in significant delays in the response of the system such that the patient has the feeling that they are pulling a heavy, bulky trolley in order to move. Such system behavior may destabilize impaired patients during walking. Moreover, some known motorized systems include a large bundle of power cables and/or control cables to power and control the trolley. Such cable bundles present significant challenges in routing and management as well as reducing the travel of the trolley. For example, in some known systems, the cable bundle is arranged in a bellows configuration such that the cable bundle collapses as the trolley moves towards the power supply and expands as the trolley moves away from the power supply. In this manner, the travel of the trolley is limited by the space occupied by the collapsed cable bundle. In some instances, the bundle of cables can constitute a varying inertia that presents significant challenges in the performance of control systems and thus, reduces the efficacy of the overall motorized support system.

Thus, a need exists for improved apparatus and methods for supporting the body-weight of a patient during gate therapy.

SUMMARY

Apparatus and methods for supporting the body weight of a patient during gait therapy are described herein. In some embodiments, a method of using the body weight support

system to provide body weight support during gait training includes defining a reference length of a tether included in the body weight support system. The tether is configured to be coupled to an attachment device worn by a user to couple the user to the body weight support system. The reference length of the tether is defined when the attachment device is in an initial position. A threshold length of the tether is defined. A first amount of body weight support is provided during the gait training as the user moves relative to a surface and the length of the tether is less than the threshold length of the tether. A second amount of body weight support is provided during the gait training as the user moves relative to the surface and the length of the tether is greater than the threshold length of the tether. The method further includes displaying data associated with the gait training on a display of an electronic device included in the body weight support system.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. **1** is a schematic illustration of a body weight support system according to an embodiment.

FIGS. **2** and **3** are perspective views of a body weight support system according to an embodiment.

FIGS. **4-7** are various perspective views of a trolley included in the body weight support system of FIG. **2**.

FIG. **8** is a top perspective view of a housing included in the trolley of FIG. **4**.

FIG. **9** is an exploded view of the housing of FIG. **8**.

FIG. **10** is an enlarged view of a portion of the trolley of FIG. **4** identified as region Z.

FIG. **11** is a bottom perspective view of an electronic system included in the trolley of FIG. **4**.

FIG. **12** is a perspective view of a drive mechanism included in the trolley of FIG. **4**.

FIGS. **13** and **14** are perspective views of a first drive assembly included in the drive mechanism of FIG. **12**.

FIGS. **15** and **16** are exploded views of the first drive assembly of FIG. **13**.

FIGS. **17-19** are perspective views of a first support member, a second support member, and a third support member, respectively, included in the first drive assembly of FIG. **13**.

FIG. **20** is an exploded view of a drive wheel subassembly included in the first drive assembly of FIG. **13**.

FIG. **21** is a perspective view of a secondary wheel subassembly included in the first drive assembly of FIG. **13**.

FIG. **22** is a perspective view of a portion of the first drive assembly of FIG. **13**, illustrating the secondary wheel subassembly of FIG. **21** coupled to the second support member of FIG. **18**.

FIG. **23** is a perspective view of the first drive assembly of FIG. **13** in contact with a support track.

FIG. **24** is a perspective view of a second drive assembly included in the drive mechanism of FIG. **12**.

FIG. **25** is an exploded view of the second drive assembly of FIG. **24**.

FIG. **26** is a perspective view of the second drive assembly of FIG. **24** in contact with the support track of FIG. **20**.

FIG. **27** is a perspective view of a support mechanism and a base included in the housing of FIG. **8** both of which are included in the trolley of FIG. **4**.

FIG. **28** is a perspective view of the support mechanism of FIG. **27**.

FIG. **29** is a perspective view of a winch assembly included in the support mechanism of FIG. **27**.

FIG. **30** is an exploded view of the winch assembly of FIG. **29**.

FIG. **31** is an exploded view of a guide assembly included in the support mechanism of FIG. **27**.

FIG. **32** is a perspective view the support mechanism of FIG. **27** shown without the winch assembly of FIG. **28**.

FIG. **33** is an exploded view of a cam assembly included in the support mechanism of FIG. **27**.

FIG. **34** is a perspective view of a patient attachment mechanism according to an embodiment.

FIG. **35** is a perspective view of a body weight support system according to an embodiment.

FIG. **36** is a cross sectional view of the body weight support system of FIG. **35** taken along the line X-X.

FIG. **37** is a schematic illustration of a support system according to an embodiment.

FIG. **38** is a perspective view of a portion of a support system according to an embodiment.

FIG. **39** is a perspective view of a push cart included in the support system of FIG. **38**.

FIG. **40** is a cross-sectional view of a connection member included in the push cart of FIG. **39**, taken along the line **40-40**.

FIGS. **41** and **42** are a top perspective view and a bottom perspective view of a portion of a support system according to an embodiment.

FIG. **43** is a perspective view of a portion of a support system according to an embodiment.

FIG. **44** is a cross-sectional view of a stopping mechanism included in the support system of FIG. **43**, taken along the line **44-44**.

FIGS. **45-47** are schematic illustrations of an optical tracking system included in a support system according to an embodiment.

FIG. **48** is a schematic illustration of a control diagram according to an embodiment.

FIG. **49** is a graph illustrating a displacement of a center of mass of a patient according to an embodiment.

FIGS. **50-53** are graphs illustrating operating conditions associated with a patient support mechanism in response to a patient's movement, according to an embodiment.

FIG. **54** illustrates graphical representations of one or more operating conditions associated with an electric stimulator and/or an impaired patient's gait while using a body weight support system, according to an embodiment.

FIG. **55** illustrates graphical representations of a set of gait characteristics of a patient, which were determined based at least in part on data associated with a body weight support system and, for example, an electric stimulator, according to an embodiment.

FIG. **56** is a screen shot of a display showing a graphical representation of data associated with a symmetry analysis of a patient's gait determined, at least in part by a body weight support system, according to an embodiment.

FIG. **57** is a screen shot of a display showing a graphical representation of data associated with a timed-up-and-go test of a patient determined, at least in part by a body weight support system, according to an embodiment.

FIG. **58** is a screen shot of a display showing a graphical representation of data associated with a timed-distance test of a patient determined, at least in part by a body weight support system, according to an embodiment.

FIG. **59** is a screen shot of a display showing a graphical representation of data associated with a fall prevention system included in and/or implemented by a body weight support system according to an embodiment.

FIGS. **60-62** are screen shots of the display graphically representing a portion of the fall prevention system illustrated in FIG. **59** in a first mode and/or configuration, a second mode and/or configuration, and a third mode and/or configuration, respectively.

FIG. **63** is a screen shot of the display graphically representing a portion of the fall prevention system illustrated in FIG. **59**.

FIGS. **64-69** are various screen shots of a display showing graphical representations of data associated with the use of a body weight support system while a patient uses a treadmill, according to an embodiment.

FIG. **70** is a schematic illustration of a portion of a support track, a portion of a power rail, and a turntable according to an embodiment.

FIG. **71** is a schematic illustration of a support system according to an embodiment.

FIGS. **72** and **73** are each a perspective view of a portion of a power system according to different embodiments.

FIGS. **74-76** are a front, side, and bottom view, respectively, of a body weight support system according to an embodiment.

FIGS. **77-79** are each a flowchart illustrating a method of providing body weight support, each according to a different embodiment.

DETAILED DESCRIPTION

In some embodiments, a method of using the body weight support system to provide body weight support during gait training includes defining a reference length of a tether included in the body weight support system. The tether is configured to be coupled to an attachment device worn by a user to couple the user to the body weight support system. The reference length of the tether is defined when the attachment device is in an initial position. A threshold length of the tether is defined. A first amount of body weight support is provided during the gait training as the user moves relative to a surface and the length of the tether is less than the threshold length of the tether. A second amount of body weight support is provided during the gait training as the user moves relative to the surface and the length of the tether is greater than the threshold length of the tether. The method further includes displaying data associated with the gait training on a display of an electronic device included in the body weight support system.

In some embodiments, a method of using a body weight support system to provide body weight support during gait training includes defining a reference length of a tether included in the body weight support system. The tether is configured to be coupled to an attachment device worn by a user to couple the user to the body weight support system. The reference length of the tether is defined when the attachment device is in an initial position. A first criterion associated with a change in a length of the tether is defined and a second criterion associated with a change in a length of the tether is defined. An amount of the body weight support to provide in response to the user falling during the gait training is defined. The method includes determining a fall has occurred based on the first criterion and the second criterion being satisfied and the amount of body weight support is provided in response to the first criterion and the second criterion being satisfied.

In some embodiments, a method of using a body weight support system to provide body weight support during gait training includes defining a reference length of a tether included in the body weight support system. The tether is configured to be coupled to an attachment device worn by a user to couple the user to the body weight support system. The reference length of the tether is defined when the attachment device is in an initial position. A threshold length of the tether is defined. The threshold length of the tether is associated with the user falling during the gait training. A threshold number of falls during the gait training is defined. The method includes providing a predetermined amount of body weight support during the gait training as the user moves relative to a surface and the number of falls is less than the threshold number of falls. The predetermined amount of body weight support to be provided to the user during the gait training is increased in response to the threshold number of falls being met. The method further includes displaying data associated with the gait training on a display of an electronic device included in the body weight support system.

In some embodiments, an apparatus includes a trolley having a drive mechanism, a patient support mechanism, and an electronic system. The drive mechanism is configured to movably suspend the trolley from a support track. The drive mechanism includes a first sensor configured to sense an operating condition of the drive mechanism. The patient support mechanism includes a tether and a second sensor. The second sensor is configured to sense an operating condition of the patient support mechanism. The tether can be operatively coupled to a patient such that the patient support mechanism supports the patient. The electronic system is configured update at least one operating condition of the drive mechanism or the patient support mechanism in response to receiving a signal from the first sensor and a signal from the second sensor such that the patient support mechanism supports a predetermined amount of the patient's body weight.

In some embodiments, an apparatus includes a drive mechanism, a patient support mechanism, and an electronic system. The drive mechanism is included in a trolley and is configured to suspend the trolley from a support track. The drive mechanism includes a first sensor configured to sense an operating condition of the drive mechanism. The patient support mechanism couples to the trolley and includes a tether and a second sensor. The tether is configured to be operatively coupled to a patient such that the patient support mechanism supports at least a portion of a weight of the patient. The second sensor is configured to sense an operating condition of the patient support mechanism. The electronic system is included in the trolley and has at least a processor and a memory. The processor is configured to define a gait characteristic of the patient based at least in part on a signal received from the first sensor and a signal received from the second sensor.

In some embodiments, a method includes receiving a signal associated with a first operating condition of at least one of a drive mechanism or a patient support mechanism. The patient support mechanism is coupled to an active trolley and configured to support a patient. The drive mechanism is coupled to the active trolley and configured to move the trolley along a support track in response to a movement of the patient. A signal associated with a second operating condition of the at least one of the drive mechanism or the patient support mechanism is received. A difference between the first operating condition and the second operating condition is determined. Based at least in part on the determining, a gait characteristic of the patient supported by the patient support mechanism is defined.

In some embodiments, a method includes receiving a first signal from a first sensor. The first signal is associated with

an operating condition of a patient support mechanism included in a patient support system. The patient support mechanism includes a tether configured to tether a patient to the patient support mechanism so that the patient support system supports at least a portion of a weight of the patient. A second signal is received from a second sensor. The second signal is associated with an operating condition of a drive mechanism included in the patient support system. The drive mechanism is configured to (1) suspend the patient support system from a support track and (2) move along the support track in response to a movement of the patient. At least one gait characteristic associated with the movement of the patient is determined based at least in part on the operating condition of the patient support mechanism and the operating condition of the drive mechanism. A third signal is sent to an output device. The third signal is indicative of an instruction to output data associated with the at least one gait characteristic via the output device.

In some embodiments, a system includes a first trolley and a second trolley movably suspended from a support track. The first trolley includes a patient attachment mechanism configured to support a first patient. The first trolley is configured to move relative to the support track. The second trolley includes a patient attachment mechanism configured to support a second patient. The second trolley is configured to move relative to the support track such that the movement of the second trolley is independent of the movement of the first trolley. A collision management assembly is configured to be coupled to one of the first trolley and the second trolley. The collision management assembly includes a bumper that is configured to prevent the first trolley from directly contacting the second trolley.

In some embodiments, an apparatus includes a coupling portion and a trolley portion. The coupling portion is coupled to an end portion of a support track. The coupling portion includes a first member and a second member. The second member is maintained in a fixed position relative to the support track, while the first member is configured to move relative to the support track to transition the coupling portion between a first configuration and a second configuration. The trolley portion is movably suspended from the support track and is coupled to an end portion of the first member. The trolley portion includes a bumper that is configured to be placed in contact with a portion of a patient support system such that when the bumper is in contact with the portion of the patient support system and the patient support system moves along the support track towards the end portion, the trolley portion is moved from a first position to a second position relative to the support track. The first member of the coupling portion is moved relative to the second member of the coupling portion as the trolley portion is moved from the first position to the second position, thereby placing the coupling portion in the second configuration. The trolley portion and the coupling portion collectively limit movement of the patient support system towards the end portion of the support track when the coupling portion is in the second configuration.

In some embodiments, an apparatus includes a trolley, a patient attachment mechanism, and a tracking member. The trolley is movably suspended from a support track. The trolley includes an electronic system having an imaging device. The electronic system is configured to control a movement of the trolley along a length of the support track. The patient attachment mechanism is coupled to the trolley and is configured to support a patient as the patient moves from a first position to a second position. The tracking member is coupled to the patient attachment mechanism and is configured to be moved relative to the trolley from a first position, associated with the first position of the patient, to a second position, associated with the second position of the patient. The imaging device of the trolley is configured to capture an image of the tracking member in its first position and an image of the tracking member in its second position the electronic system is configured to control the movement of the trolley along the length of the support track based at least in part on the image of the tracking member in its first position and the image of the tracking member in its second position.

In some embodiments, a body weight support system includes a trolley, a power rail operative coupled to a power supply, and a patient attachment mechanism. The trolley can include a drive system, a control system, and a patient support system. The drive system is movably coupled to a support rail. At least a portion of the control system is physically and electrically coupled to the power rail. The patient support mechanism is at least temporarily coupled to the patient attachment mechanism. The control system can control at least a portion of the patient support mechanism based at least in part on a force applied to the patient attachment mechanism.

In some embodiments, a body weight support system includes a closed loop tack, a powered conductor coupled to the closed loop track, an actively controlled trolley, and a patient support assembly. The actively controlled trolley is movably suspended from the closed loop track and is electrically coupled to the powered conductor. The patient support assembly is coupled to the trolley and is configured to dynamically support a body weight of a patient.

In some embodiments, a body weight support device includes a housing, a drive element, a wheel assembly, and a patient support assembly. At least a portion of the drive element and at least portion of the wheel assembly is disposed within the housing. The patient support assembly is coupled to the drive element and is configured to dynamically support a body weight of a patient.

As used in this specification, the singular forms "a," "an" and "the" include plural referents unless the context clearly dictates otherwise. Thus, for example, the term "a member" is intended to mean a single member or a combination of members, "a material" is intended to mean one or more materials, or a combination thereof.

As used herein, the terms "about" and "approximately" generally mean plus or minus 10% of the value stated. For example, about 0.5 would include 0.45 and 0.55, about 10 would include 9 to 11, about 1000 would include 900 to 1100.

As used herein, the term "set" can refer to multiple features or a singular feature with multiple parts. For example, when referring to set of walls, the set of walls can be considered as one wall with multiple portions, or the set of walls can be considered as multiple, distinct walls. Thus, a monolithically constructed item can include a set of walls. Such a set of walls may include multiple portions that are either continuous or discontinuous from each other. For example, a monolithically constructed wall can include a set of detents can be said to form a set of walls. A set of walls can also be fabricated from multiple items that are produced separately and are later joined together (e.g., via a weld, an adhesive, or any suitable method).

As used herein, the term "parallel" generally describes a relationship between two geometric constructions (e.g., two lines, two planes, a line and a plane or the like) in which the two geometric constructions are substantially non-intersecting as they extend substantially to infinity. For example, as

used herein, a line is said to be parallel to another line when the lines do not intersect as they extend to infinity. Similarly, when a planar surface (i.e., a two-dimensional surface) is said to be parallel to a line, every point along the line is spaced apart from the nearest portion of the surface by a substantially equal distance. Two geometric constructions are described herein as being "parallel" or "substantially parallel" to each other when they are nominally parallel to each other, such as for example, when they are parallel to each other within a tolerance. Such tolerances can include, for example, manufacturing tolerances, measurement tolerances or the like.

As used herein, the term "tension" is related to the internal forces (i.e., stress) within an object in response to an external force pulling the object in an axial direction. For example, an object with a mass being hung from a rope at one end and fixedly attached to a support at the other end exerts a force to place the rope in tension. The stress within an object in tension can be characterized in terms of the cross-sectional area of the object. For example, less stress is applied to an object having a cross-sectional area greater than another object having a smaller cross-sectional area. The maximum stress exerted on an object in tension prior to plastic deformation (e.g., permanent deformation such as, for example, necking and/or the like) is characterized by the object's tensile strength. The tensile strength is an intensive property of (i.e., is intrinsic to) the constituent material. Thus, the maximum amount of stress of an object in tension can be increased or decreased by forming the object from a material with a greater tensile strength or lesser tensile strength, respectively.

As used herein, the term "kinematics" describes the motion of a point, object, or system of objects without considering a cause of the motion. For example, the kinematics of an object can describe a translational motion, a rotational motion, or a combination of both translational motion and rotational motion. When considering the kinematics of a system of objects, known mathematical equations can be used to describe to the motion of an object relative to a plane or set of planes, an axis or set of axes, and/or relative to one or more other objects included in the system of objects.

As used herein, the terms "feedback", "feedback system", and/or "feedback loop" relate to a system wherein past or present characteristics influence current or future actions. For example, a thermostat is said to be a feedback system wherein the state of the thermostat (e.g., in an "on" configuration or an "off" configuration) is dependent on a temperature being fed back to the thermostat. Feedback systems can include a control scheme such as, for example, a proportional-integral-derivative (PID) controller. Expanding further, an output of some feedback systems can be described mathematically by the sum of a proportional term, an integral term, and a derivative term. PID controllers are often implemented in one or more electronic devices. In such controllers, the proportional term, the integral term, and/or the derivative term can be actively "tuned" to alter characteristics of the feedback system.

Electronic devices often implement feedback systems to actively control the kinematics of mechanical systems in order to achieve and/or maintain a desired system state. For example, a feedback system can be implemented to control a force within a system (e.g., a mass-spring system and/or the like) by changing the kinematics and/or the position of one or more components relative to any other components included in the system. Expanding further, the feedback system can determine current and/or past states (e.g., position, velocity, acceleration, force, torque, tension, electrical power, etc.) of one or more components included in the mechanical system and return the past and/or current state values to, for example, a PID control scheme. In some instances, an electronic device can implement any suitable numerical method or any combination thereof (e.g., Newton's method, Gaussian elimination, Euler's method, LU decomposition, etc.). Thus, based on the past and/or current state of the one or more components, the mechanical system can be actively changed to achieve a desired system state.

FIG. **1** is a schematic illustration of a body weight support system **1000** according to an embodiment. The body weight support system **1000** (also referred to herein as "support system") includes at least a trolley **1100**, a patient attachment mechanism **1800** (also referred to herein as "attachment mechanism"), a power supply **1610**, a powered conductor or rail **1620**, and a control **1900**. The support system **1000** can be used, for example, in intensive gait therapy to support patients with walking deficiencies brought on by neurological injuries such as stroke, spinal cord injury, traumatic brain injury, or the like. In such instances, the support system **1000** can be used to support at least a portion of the patient's body weight to facilitate the gait therapy. In other instances, the support system **1000** can be used to simulate, for example, low gravity scenarios for the training of astronauts or the like. In some embodiments, the support system **1000** can be used to support a patient over a treadmill or stairs instead of or in addition to supporting a patient over and across level ground.

The trolley **1100** included in the support system **1000** can be any suitable shape, size, or configuration and can include one or more systems, mechanisms, assemblies, or subassemblies (not shown in FIG. **1**) that can perform any suitable function associated with, for example, supporting at least a portion of the body weight of a patient. The trolley **1100** can include at least a drive system **1300**, a patient support mechanism **1500**, and an electronic system **1700**. In some embodiments, the drive system **1300** can be movably coupled to a support track (not shown in FIG. **1**) and configured to move (e.g., slide, roll, or otherwise advance) along a length of the support track. The support track can be any suitable shape, size, or configuration. For example, in some embodiments, the support track can be substantially linear or curvilinear. In other embodiments, the support track can be a closed loop such as, for example, circular, oval, oblong, rectangular (e.g., with or without rounded corners), or any other suitable shape. In some embodiments, the support track can be a beam (e.g., an I-beam or the like) included in a roof or ceiling structure from which at least a portion of the trolley **1100** can "hang" (e.g., at least a portion of the trolley **1100** can extend away from the beam). In other embodiments, at least one end portion of the support track can be coupled to a vertical wall or the like. In still other embodiments, the support track can be included in a free-standing structure such as, for example, a gantry or an A-frame.

The drive system **1300** of the trolley **1100** can include one or more wheels configured to roll along a surface of the support track such that the weight of the trolley **1100** and a portion of the weight of a patient utilizing the support system **1000** (e.g., the patient is temporarily coupled to the trolley **1100** via the patient attachment mechanism **1800**, as described in further detail herein) are supported by the support track. Similarly stated, one or more wheels of the drive system **1300** can be disposed adjacent to and on top of a horizontal surface of the support track; thus, the trolley **1100** can be "hung" from or suspended from the support

track. In other embodiments, the surface from which the trolley **1100** is hung need not be horizontal. For example, at least a portion of the support track can define a decline (and/or an incline) wherein a first end portion of the support track is disposed at a first height and a second end portion of the support track is disposed at a second height, different from the first height. In such embodiments, the trolley **1100** can be hung from a surface of the support track that is parallel to a longitudinal centerline (not shown) of the trolley **1100**. In such embodiments, the trolley can be used to support a patient moving across an inclined/declined surface, up or down stairs, etc.

In some embodiments, the trolley **1100** can have or define a relatively small profile (e.g., height) such that the space between a surface of the trolley **1100** and a portion of the patient can be sufficiently large to allow the patient to move between a seated position to a standing position such as, for example, when a patient rises out of a wheelchair. Furthermore, with the trolley **1100** being hung from the support track, the weight of the trolley **1100** and the weight of the patient utilizing the support system can increase the friction (e.g., traction) between the one or more wheels of the drive system and the surface of the support track from which the trolley **1100** is hung. Thus, the one or more wheels of the drive system **1300** can roll along the surface of the support track without substantially slipping.

In some embodiments, the trolley **1100** can be motorized. For example, in some embodiments, the trolley **1100** can include one or more motors configured to power (e.g., drive, rotate, spin, engage, activate, etc.) the drive system **1300**. In some embodiments, the motor(s) can be configured to rotate the wheels of the drive system **1300** at any suitable rate and/or any suitable direction (e.g., forward or reverse) such that the trolley **1100** can pace a patient utilizing the support system **1000**, as described in further detail herein. In some embodiments, the electronic system **1700** and/or the control **1900** can be operatively coupled (e.g., electrically connected) to the one or more motors such that the electronic system **1700** and/or the control **1900** can send an electronic signal associated with operating the motor(s). In some embodiments, the motor(s) can include a clutch, a brake, or the like configured to substantially lock the motor(s) in response to a power failure or the like. Similarly stated, the motor(s) can be placed in a locked configuration to limit movement of the trolley **1100** (e.g., limit movement of the drive system **1300** and/or the patient support mechanism **1500**) in response to a power failure (e.g., a partial power failure and/or a total power failure).

The patient support mechanism **1500** (also referred to herein as "support mechanism") can be any suitable configuration and can be at least temporarily coupled to the attachment mechanism **1800**. For example, in some embodiments, the support mechanism **1500** can include a tether that can be temporarily coupled to a coupling portion of the attachment mechanism **1800**. Moreover, the attachment mechanism **1800** can further include a patient coupling portion (not shown in FIG. **1**) configured to receive a portion of a harness or the like worn by or coupled to the patient. Thus, the attachment mechanism **1800** and the support mechanism **1500** can support a portion of the body weight of a patient and temporarily couple the patient to the trolley **1100**.

In some embodiments, an end portion of the tether can be coupled to, for example, a winch. In such embodiments, the winch can include a motor that can rotate a drum to coil or uncoil the tether. Similarly stated, the tether can be wrapped around the drum and the motor can rotate the drum in a first direction to wrap more of the tether around the drum and can rotate the drum in a second direction, opposite the first direction, to unwrap more of the tether from around the drum. In some embodiments, the support mechanism **1500** can include one or more pulleys that can engage the tether such that the support mechanism **1500** gains a mechanical advantage. Similarly stated, the pulleys can be arranged such that the force exerted by the winch to coil or uncoil the tether around the drum while a patient is coupled to the attachment mechanism **1800** is reduced.

The horizontal drive system/motor that is configured to allow for movement of the trolley along the track, and the vertical drive system configured to move to control the tether can be simultaneously controlled and operated or not. For example, when a patient is walking over a treadmill, there is little or no horizontal movement, but the vertical (weight bearing) drive system is operational to compensate for the changes during the gait, falls, etc.

In some embodiments, the pulley system can include at least one pulley that is configured to move (e.g., pivot, translate, swing, or the like). For example, the pulley can be included in or coupled to a cam mechanism (not shown) that is configured to define a range of motion of the pulley. In such embodiments, the movement of the at least one pulley can coincide and/or be caused by a force exerted on the attachment mechanism **1800**. For example, in some instances, the patient can move relative to the trolley **1100** such that the force exerted on the tether by the weight of the patient is changed (e.g., increased or decreased). In such instances, the pulley can be moved according to the change in the force such that the tension within the tether is substantially unchanged. Moreover, with the pulley included in or coupled to the cam mechanism, the movement of the pulley can move the cam through a predetermined range of motion. In some embodiments, the electronic system **1700** can include a sensor or encoder operatively coupled to the pulley and/or the cam that is configured to determine the amount of movement of the pulley and/or the cam. In this manner, the electronic system **1700** can send a signal to the motor included in the winch associated with coiling or uncoiling the tether around the drum in accordance with the movement of the pulley. For example, the pulley can be moved in a first direction in response to an increase in force exerted on the tether and the electronic system **1700** can send a signal to the motor of the winch associated with rotating the drum to uncoil a portion of the tether from the drum. Conversely, the pulley can be moved in a second direction, opposite the first direction, in response to a decrease in force exerted on the tether and the electronic system **1700** can send a signal to the motor of the winch associated with rotating the drum to coil a portion of the tether about the drum. Thus, the support mechanism **1500** can be configured to exert a reaction force in response to the force exerted by the patient such that the portion of the body weight supported by the support system **1000** remains substantially unchanged. Moreover, by actively supporting the portion of the body weight of the patient, the support system **1000** can limit the likelihood and/or the magnitude of a fall of the patient supported by the support system **1000**. Similarly stated, the support mechanism **1500** and the electronic system **1700** can respond to a change in force exerted on the tether in a relatively short amount of time (e.g., much less than a second) to actively limit the magnitude of the fall of the patient.

As described above, the electronic system **1700** included in the trolley **1100** can control at least a portion of the trolley **1100**. The electronic system **1700** includes at least a pro-

cessor and a memory. The memory can be, for example, a random access memory (RAM), a memory buffer, a hard drive, a read-only memory (ROM), an erasable programmable read-only memory (EPROM), and/or the like. In some embodiments, the memory stores instructions to cause the processor to execute modules, processes, and/or functions associated with controlling one or more mechanical and/or electrical systems included in the patient support system **1000**, as described above. In some embodiments, control signals are delivered through the powered rail using, for example, a broadband over power-line (BOP) configuration.

The processor of the electronic device can be any suitable processing device configured to run or execute a set of instructions or code. For example, the processor can be a general-purpose processor (GPU), a central processing unit (CPU), an accelerated processing unit (APU), and/or the like. The processor can be configured to run or execute a set of instructions or code stored in the memory associated with controlling one or more mechanical and/or electrical systems included in a patient support system **1000**. For example, the processor can run or execute a set of instructions or code associated with controlling one or more motors, sensors, communication devices, encoders, or the like, as described above. More specifically, the processor can execute a set of instructions in response to receiving a signal from one or more sensors and/or encoders associated with a portion of the drive system **1300** and/or the support mechanism **1500**. Similarly stated, the processor can be configured to execute a set of instructions associated with a feedback loop (e.g., based on a proportional-integral-derivative (PID) control method) wherein the electronic system **1700** can control the subsequent action of the drive system **1300** and/or the support system **1500** based at least in part on current and/or previous data (e.g., position, velocity, force, acceleration, angle of the tether, or the like) received from the drive system **1300** and/or the support system **1500**, as described in further detail herein.

In some embodiments, the electronic system **1700** can include a communication device (not shown in FIG. **1**) that can be in communication with the control **1900**. For example, in some embodiments, the communication device can include one or more network interface devices (e.g., a network interface card). The communication device can be configured to transmit data over a wired and/or wireless network (not shown in FIG. **1**) associated with sending data to and/or receiving data from the control **1900**. The control **1900** can be any suitable device or module (e.g., hardware module or software module stored in the memory and executed in the process). For example, in some embodiments, the control **1900** can be an electronic device that includes at least a processor and a memory (not shown in FIG. **1**) and is configured to run, for example, a personal computer application, a mobile application, a web page, and/or the like. In this manner, a user can engage the control **1900** to establish a set of system parameters associated with the support system **1000**, as described in further detail herein. In some embodiments, the control **1900** can be implemented as a handheld controller.

In some embodiments, control of the trolley **1100** can be accomplished using one or more controllers. In embodiments in which multiple controllers are utilized (e.g., a personal computer control and a handheld control), only one controller can be used at a time. In other embodiments, one of the controllers (e.g., the handheld controller) can override the personal computer controller. In other embodiments, a user can designate which controller is utilized by actuating the relevant controller. In other words, the user either can take control using a controller or can pass control to the other controller by actuating the controller.

In some embodiments, the patient support system **1000** is configured to improve gait and stability rehabilitation training by adding visual and audio feedback to a gait and stability assistance device. The trolley **1100** coordinates the feedback with heuristic patient data from past training sessions, and stores the data for each therapy/training.

As shown in FIG. **1**, the trolley **1100** is operatively coupled to the power rail **1620**. The power rail **1620** is further coupled to the power source **1610** that is configured to provide a flow of electrical current (e.g., electrical power) to the power rail **1620**. More specifically, the power rail **1620** can include any suitable transformer, converter, conditioner, capacitor, resistor, insulator, and/or the like (not shown in FIG. **1**) such that the power rail **1620** can receive the flow of electrical current from the power source **1610** and transfer at least a portion of the flow of electrical current to the trolley **1100**. The power rail **1620** can include one or more electrical conductors to deliver, for example, single or multiphase electrical power to one or more trolleys **1100**. For example, in some embodiments, the power rail **1620** is a substantially tubular rail configured to receive a conductive portion of the electronic system **1600** of the trolley **1100**. In such embodiments, the power rail **1620** can include one or more conductive surfaces disposed within an inner portion of the tubular rail along which a conductive member of the electronic system **1700** can move (e.g., slide, roll, or otherwise advance). In other embodiments, the power rail **1620** can be and/or can have a substantially open configuration (e.g., is not substantially tubular). In such embodiments, the power rail **1620** can include one or more conductive members disposed on any suitable surface or combination of surfaces of the power rail **1620**.

The power rail **1620** is configured to transmit a flow of electrical current from the power source **1610** to the electronic system **1700** of the trolley **1100**, as described in further detail herein. The power rail **1620** can be any suitable shape, size, or configuration. For example, the power rail **1620** can extend in a similar shape as the support track (not shown in FIG. **1**) and can be arranged such that the power rail **1620** is substantially parallel to the support track. In this manner, the trolley **1100** can advance along a length of the support track while remaining in electrical contact with the power rail **1620**. Furthermore, the arrangement of the power rail **1620** and the trolley **1100** is such that movement of the trolley **1100** along the length of the support track is not hindered or limited by a bundle of cables, as described above with reference to known support systems. In other embodiments, the power rail **1620** and/or a portion thereof can be coupled to, disposed along, and/or otherwise at least partially integrated with the support track or a portion thereof. In still other embodiments, the power rail **1620** can be and/or can have a telescoping configuration in which the power rail **1620** extends, for example, from a central power source to the trolley **1100**.

Although described above as being coupled to a power rail **1620**, in some embodiments, the trolley **1100** can be battery powered. In such embodiments, the trolley **1100** can include one or more batteries or a battery system that is suitable for providing the trolley **1100** with a flow of electrical current. In such embodiments, the battery or batteries can be configured to provide electric power in addition to and/or instead of electric power received from the power rail **1620**. In some embodiments, the battery or batteries included in such embodiments can be rechargeable.

For example, at least a portion of the flow of electric power or electric current received from the power rail **1620** can be delivered to the battery or batteries (e.g., to charge or re-charge the battery). In some embodiments, the power rail **1620** and/or support track can include one or more charging station(s) located in certain location(s) on or along the support track. In such embodiments, the trolley **1100** can, for example, automatically dock to the charging station(s) according to a predetermined or desired algorithm, schedule, and/or condition. For example, the trolley may travel to and dock with such a charging station when a power level of one or more batteries is below predetermined and/or desired level or during the break periods (for example when the system is not in use for a given time, at night, or at predetermined times).

While the trolley **1100** is described above as receiving electric power from one or more of the power rail **1620** or a battery or battery system, in some embodiments, the support system **1000** can include an uninterruptible power supply (or any other suitable energy capacitor or energy storage device) that can provide electric power to at least a portion of the support system **1000**. For example, in some embodiments, an uninterruptible power supply (UPS) can be included to provide a backup to the power supply **1610** and/or one or more batteries included in the trolley **1100**. That is to say, the UPS can be electrically connected between the power source **1610** and the power rail **1620** or the power source **1610** and the trolley **1100**. In other embodiments, the UPS can be configured to provide electric power to the power supply **1610**, for example, in response to a power grid failure and/or interruption. That is to say, the UPS can be electrically connected between the power grid and the power source **1610**. In still other embodiments, the trolley **1100** can include a UPS that can provide electric power to the trolley **1100** if a flow of electric power from the power rail **1620** or from one or more batteries is interrupted or otherwise stops. In some embodiments, the support system **1000** can include a UPS configured to provide primary or backup power to the trolley **1100** and one or more additional devices included in the support system **1000** (e.g., a secondary training device such as a treadmill, one or more compute devices such as a personal computer, server, etc., and/or any other suitable device).

In some embodiments, electric power and/or energy can be transferred from the power rail **1620** (or one or more portions of the power rail **1620**) to the trolley **1100** via any suitable mode of transfer. For example, in some embodiments, a conductive member of the trolley **1100** (e.g., a collector or the like) can be in physical and/or electrical contact with a conductor or conductive portion of the power rail **1620**. In other embodiments, the trolley **1100** can include one or more induction coils along which a flow of electric current is induced in response to an alternating electromagnetic field generated by or along at least a portion the power rail **1620** and/or a conductive portion or surface of the track **1050**. In such embodiments, electric power received via induction can be used to provide electric power for the trolley **1100** and/or can be used to, for example, charge one or more batteries of the trolley **1100**.

Moreover, the control **1900** can also be operatively coupled to the power supply **1610** and can be configured to control the amount of power delivered to the power rail **1620** and/or the trolley **1100**. For example, the control **1900** can be configured to begin a flow of electrical current from the power supply **1610** to the power rail **1620** to turn on or power up the support system **1000**. Conversely, the control **1900** can be configured to stop a flow of electrical current from the power supply **1610** to the power rail **1620** to turn off or power down the support system **1000**.

While the control **1900** is shown in FIG. **1** as being independent from and operatively coupled to the trolley **1100**, in some embodiments, the control **1900** can be included in the electronic system **1700** of the trolley **1100**. For example, in some embodiments, the control **1900** can be a hardware module and/or a software module that can be executed by the processor of the electronic system **1700**. In such embodiments, the electronic system **1700** can include a user interface (e.g., a touch screen and/or one or more dials, buttons, switches, toggles, or the like). Thus, a user (e.g., a physical therapist, a doctor, a nurse, a technician, etc.) can engage the user interface associated with the control **1900** to establish a set of system parameters for the support system **1000**.

Although not shown in FIG. **1**, in some embodiments, more than one trolley **1100** can be coupled to the same support track. In such embodiments, the trolleys **1100** hung from the support track can include, for example, sensors (e.g., ultrasonic proximity sensors and/or the like) that can send a signal to the electronic system **1700** associated with the proximity of one or more trolleys **1100** relative to a specific trolley **1100**. In this manner, the electronic system **1700** of the trolleys **1100** can control, for example, a motor included in the drive system **1300** to prevent collision of the trolleys **1100**. Thus, the support system **1000** can be used to support more than one patient (e.g., a number of patients corresponding to a number of trolleys **1100** disposed about the support track) while keeping the patients at a desired distance from one another.

In some embodiments, the support system is configured to provide feedback to a patient during use. In some embodiments, a laser or culminated light source is coupled to the trolley **1100** to create a light path for a patient to follow during a session. The light path allows the patient to look ahead or look at their feet while attempting to train their brain to properly control the leg/foot/hip motion. In some embodiments, a second light source is configured to illuminate a "target" location at which the patient can aim to plant their foot in a proper location. In some embodiments, the size of the target can be varied depending upon the dexterity of the user. In other words, for a user with greater muscle control, the target can be smaller. The light path and target location can be modified using a user interface as described in greater detail herein.

In some embodiments, audible feedback is provided to the patient when the patient's gate is incorrect. In some embodiments, audible feedback can be provided when the patient begins to fall. Different audible tones can be provided for different issues/purposes.

In some embodiments, a CCD camera interface is configured for video monitoring for future analysis and can be correlated to sensed rope position, speed, tension, etc. In some embodiments, monitors can be coupled to a patient's body to monitor muscle usage (e.g., leg muscles, torso muscles, etc.). Such information can be wirelessly transmitted to the electronic system **1700** and coordinated in the feedback provided to the patient during and after a therapy/rehabilitation session. Said another way, all of the data collected by the various sensors, cameras, etc. can be coordinated to provided dynamic, real-time feedback and/or post-session feedback.

FIGS. **2-33** illustrate a body weight support system **2000** according to an embodiment. The body weight support system **2000** (also referred to herein as "support system") can be used to support a portion of a patient's body weight,

for example, during gait therapy or the like. FIGS. **2** and **3** are perspective views of the support system **2000**. The support system **2000** includes a trolley **2100**, a power system **2600**, and a patient attachment mechanism **2800** (see e.g., FIG. **34**). As shown in FIGS. **2** and **3**, the trolley **2100** is movably coupled to a support track **2050** that is configured to support the weight of the trolley **2100** and the weight of the patient utilizing the support system **2000**. Although the support track **2050** is shown as having an I-shape, the support track **2050** can be any suitable shape. Furthermore, while the support track **2050** is shown as being substantially linear, the support track **2050** can extend in a curvilinear direction. In other embodiments, the support track **2050** can be arranged in a closed loop such as, for example, circular, oval, oblong, square, or the like. As described in further detail herein, the power system **2600** can include a power rail **2620** that extends substantially parallel to the support track **2050** and is at least electrically coupled to the trolley **2100** to transfer a flow of electrical current from a power source (not shown in FIGS. **2-32**) to the trolley **2100**.

FIGS. **4-7** are perspective views of the trolley **2100**. The trolley **2100** can be any suitable shape, size, or configuration. For example, the trolley **2100** can suspended from the support track **2050** (as described in further detail herein) and can have or define a relatively small profile (e.g., height) such that the space between the trolley **2100** and a patient can be maximized. In this manner, the support system **2000** can be used to support patients of varying heights as well as supporting a patient rising from a sitting position to a standing position as is common in assisting patient at least partially relegated to a wheelchair. The trolley **2100** includes a housing **2200** (see e.g., FIGS. **8** and **9**), an electronic system **2700** (see e.g., FIGS. **10** and **11**), a drive system **2300** (see e.g., FIGS. **12-26**), and a patient support mechanism **2500** (see e.g., FIGS. **27-33**).

As shown in FIGS. **8** and **9** the housing **2200** includes a base **2210**, a first side member **2230**, a second side member **2240**, a third side member **2250**, and a cover **2260**. The housing **2200** is configured to enclose and/or cover at least a portion of the electronic system **2700**, as described in further detail herein. As shown in FIG. **9**, the base **2210** has a first side **2211** and a second side **2212**. The base **2210** defines a set of drive mechanism openings **2213**, a fan opening **2214**, a guide mechanism opening **2215**, a bias mechanism opening **2217**, a guide member opening **2218**, and a cam pulley opening **2219**, a cam pivot opening **2220**. As described in further detail herein, the drive mechanism openings **2213** receive at least a portion of a first drive assembly **2310** included in the drive mechanism **2300** such that a set of wheels included therein can rotate without contacting the base **2210**. The fan opening **2214** is receives a portion of a fan **2740** included in the electronic system **2700**. More specifically, a portion of the fan **2740** can extend through the opening such that the fan can remove heat from within the housing **2200** produced by the electronic system **2700**. The guide mechanism opening **2215** receives a portion of a guide mechanism **2540** included in the patient support mechanism **2500** (also referred to herein as "support mechanism"). More specifically, the base **2210** includes a set of mounting tabs **2216** configured to extend from a surface of the base **2210** that defines the guide mechanism opening **2215**. In this manner, the guide mechanism **2540** can be coupled to the mounting tabs **2216**. The bias mechanism opening **2217**, the guide member opening **2218**, the cam pulley opening **2219**, and the cam pivot opening **2220** can each movably receive a portion of a cam mechanism **2570** included in the support mechanism **2500**, as described in further detail herein.

The first side member **2230** has a first side **2231** and a second side **2232**. The second side **2232** defines a slot **2233** that receives a portion of the base **2210** to couple the base **2210** thereto. The first side member **2230** also includes a mounting portion **2235** that is coupled to a portion of a collector **2770** included in the electronic system **2700**, as described in further detail herein. The second side member **2240** has a first side **2241** and a second side **2242**. The second side **2242** defines a slot **2243** that receives a portion of the base **2210** to couple the base **2210** thereto. The second side **2242** also includes a recessed portion **2244** that is coupled to a portion of a winch assembly **2510** included in the support mechanism **2500**. The third side member **2250** is coupled to the first side member **2230**, the second side member **2240**, and the base **2210** and defines a light opening **2251** that receives an indicator light and a power outlet opening that receives a power outlet module.

The cover **2260** is disposed adjacent to the second side **2212** of the base **2210**. More specifically, the cover **2260** can be removably coupled to the second side **2212** of the base **2210** such that the portion of the electronic system **2700** enclosed therein can be accessed. The cover **2260** has a first end portion **2261** and a second end portion **2262**. The first end portion **2261** is open-ended and defines a notch **2265** configured to receive a portion of the collector **2770**, as described in further detail herein. The second end portion **2262** of the cover **2260** is substantially enclosed and is configured to include a recessed region **2264**. In this manner, a portion of the support mechanism **2500** can extend into and/or through the recessed region **2264** to couple to the patient attachment mechanism **2800**, as described in further detail herein. The cover **2260** also defines a set of vents **2263** that can be arranged to provide a flow of air into the area enclosed by the cover **2260** such that at least a portion of the electronic system **2700** disposed therein can be cooled.

FIGS. **10** and **11** illustrate the electronic system **2700** of the trolley **2100**. The electronic system **2700** includes a set of electronic devices that are collectively operated to control at least a portion of the trolley **2100**. As described above, the electronic system **2700** includes the collector **2770** that is coupled to a portion of the housing **2200** and that is placed in physical and/or electrical contact with the power rail **2620**. The collector **2770** can be any suitable shape, size, or configuration and can be formed from any suitable conductive material, such as, for example, iron, steel, or the like. In this manner, the collector **2770** can receive a flow of electrical current from the power rail **2620**. For example, as shown in FIG. **10**, the power rail **2620** is a substantially hollow tube that houses or substantially encloses one or more conductive portions **2621** (e.g., individual conductors or surfaces) that are electrically coupled to a power source (not shown). In this manner, the collector **2770** can be disposed within the hollow tube of the power rail **2620** such that a conductive portion **2771** (e.g., individual conductors, a conductive surface, or the like) of the collector **2770** is placed in electrical communication with the one or more conductive portions **2621** of the power rail **2620**. Thus, the collector **2770** receives a flow of current from the power source and transferred by the power rail **2620**. Moreover, the collector **2770** can be disposed within the power rail **2620** such that a coupling portion **2772** of the collector **2770** extends through a slot **2622** defined by the power rail **2620** to be coupled to the mounting portion **2235** of the housing **2200**. The coupling portion **2772** can further be coupled to

a power module (not shown) of the trolley **2100**. Thus, the trolley **2100** receives power from the power source via the power rail **2620**.

While the power rail **2620** is shown and described as being a substantially hollow tube, in other embodiments, a power rail can be any suitable configuration. For example, in some embodiments, a power rail can be one or more conductive portions on any suitable surface such as a surface of a relative flat or open power rail. In some embodiments, the power rail can be one or more conductive portions of, for example, the support track **2050** (e.g., one or more inner surface and/or one or more outer surface). As described in further detail herein, a conductive portion of the trolley **2100** (e.g., the collector **2770**) can be in electric contact with the power rail **2620** and/or any other suitable conductive surface providing a flow of electric power, which in turn, powers one or more portions of the trolley **2100**.

While not shown in FIGS. **10** and **11**, the electronic system **2700** includes at least a processor, a memory, and a communication device. The memory can be, for example, a random access memory (RAM), a memory buffer, a hard drive, a read-only memory (ROM), an erasable programmable read-only memory (EPROM), and/or the like. In some embodiments, the memory stores instructions to cause the processor to execute modules, processes, and/or functions associated with controlling one or more mechanical and/or electrical systems included in the patient support system **2000**. For example, the memory can store instructions, information, and/or data associated with a proportion-integral-derivative (PID) control system. In some embodiments, the PID control system can be included in, for example, a software package. In some embodiments, the PID control can be a set of user controlled instructions executed by the processor that allow the user to "tune" the PID control, as described in further detail herein.

The processor of the electronic device can be any suitable processing device configured to run or execute a set of instructions or code. For example, the processor can be a general-purpose processor (GPU), a central processing unit (CPU), an accelerated processing unit (APU), and/or the like. The processor can be configured to run or execute a set of instructions or code stored in the memory associated with controlling one or more mechanical and/or electrical systems included in a patient support system. For example, the processor can run or execute a set of instructions or code associated with the PID control stored in the memory and further associated with controlling with a portion of the drive system **2300** and/or the patient support mechanism **2500**. More specifically, the processor can execute a set of instructions in response to receiving a signal from one or more sensors and/or encoders (shown and described below) that can control one or more subsequent actions of the drive system **2300** and/or the support mechanism **2500**. Similarly stated, the processor can execute a set of instructions associated with a feedback loop that includes one or more sensors or encoders that send a signal that is at least partially associated with current and/or previous data (e.g., position, velocity, force, acceleration, or the like) received from the drive system **2300** and/or the support mechanism **2500**, as described in further detail herein.

The communication device can be, for example, one or more network interface devices (e.g., network cards) configured to communicate with an electronic device over a wired or wireless network. For example, in some embodiments, a user can manipulate a remote control device that sends one or more signals to and/or receives one or more signals from the electronic system **2700** associated with the operation of the trolley **2100**. The remote control can be any suitable device or module (e.g., hardware module or software module stored in the memory and executed in the process). For example, in some embodiments, the remote control can be an electronic device that includes at least a processor and a memory and that runs, for example, a personal computer application, a mobile application, a web page, and/or the like. In this manner, a user can engage the remote control to establish a set of system parameters associated with the support system **2000** such as, for example, the desired amount of body weight supported by the support system **2000**.

As shown in FIG. **12**, the drive system **2300** includes a first drive assembly **2310** and a second drive assembly **2400**. The drive system **2300** is coupled to the first side **2211** of the base **2210** (see e.g., FIGS. **2** and **3**) and arranged such that the first drive assembly **2310** and the second drive assembly **2400** are aligned (e.g., coaxial). In this manner, the first drive assembly **2310** and the second drive assembly **2400** can receive a portion of the support track **2050**, as described in further detail herein.

FIGS. **13-23** illustrate the first drive assembly **2310**. The first drive assembly **2310** includes a motor **2311**, a support structure **2315**, a set of guide wheel assemblies **2360**, a set of drive wheel assemblies **2370**, and a set of secondary wheel assemblies **2390**. The motor **2311** is coupled to a side member **2320** of the support structure **2315** and is in electrical communication with a portion of the electronic system **2700**. The motor **2311** includes an output shaft **2312** (see e.g., FIGS. **15** and **16**) that engages a portion of one of the drive wheel assemblies **2370** to rotate a drive wheel **2385** included therein. More specifically, the motor **2311** receives an activation signal (e.g., a flow of electrical current) from the electronic system **2700** to cause the motor **2311** to rotate the output shaft **2312**, which, in turn, rotates the drive wheel **2385**. As shown in FIGS. **13** and **14**, at least a portion of the first drive assembly **2310** is substantially symmetrical about a longitudinal plane (not shown) defined by the first drive assembly **2310**. In this manner, each side of the first drive assembly **2310** includes similar components, thereby increasing versatility and decreasing manufacturing costs. For example, while the first drive assembly **2310** is shown including two side members **2320** with the motor **2311** being coupled to a particular side member **2320**, in other embodiments, the motor **2311** can be coupled to the other side member **2320**.

The support structure **2315** includes two side members **2320**, a base **2340**, two leading support members **2350**, two trailing support members **2354**, and two transverse support members **2358**. As shown in FIGS. **13-16**, the side members **2320** are the same (e.g., due to the symmetry of the first drive assembly **2310**). The side members **2320** each define a bearing opening **2321**, a notch **2322**, and a set of slots **2325**. The bearing opening **2321** of each side member **2320** receives a drive bearing **2376** (FIG. **20**) included in the drive wheel assembly **2370**. More specifically, the drive bearing **2376** can be disposed within the bearing opening **2321** such that an outer surface of the drive bearing **2376** forms a friction fit with a surface of the side member **2320** that defines the bearing opening **2321**. Similarly stated, the drive bearing **2376** and the surface of the side **2320** defining the bearing opening **2321** form a press fit to retain the drive bearing **2376** within the bearing opening **2321**.

The notch **2322** defined by each of the side members **2320** receives a spring rod **2323** and a spring **2324**. The spring **2324** is disposed about the spring rod **2323** such that the spring rod **2323** substantially limits the motion of the spring

2324. More specifically, the spring rod **2323** is configured to allow the spring **2324** to move in an axial direction (e.g., compress and/or expand) while substantially limiting movement of the spring **2324** in a transverse direction. As described in further detail herein, the spring rod **2323** and the spring **2324** extend from a surface of the notch **2322** to engage a spring protrusion **2344** of the base **2340**. The set of slots **2325** is configured such that each slot **2325** receives mounting hardware (e.g., a mechanical fastener, a pin, a dowel, etc.) configured to movably couple the side members **2320** to the base **2340**, as described in further detail herein.

As described above, the base **2340** is movably coupled to the side members **2320**. The base **2340** includes a set of sidewalls **2342**, and an axle portion **2346**. The axle portion **2346** of the base **2340** defines an opening **2347** that receives a transfer axle **2388** included in the drive wheel assembly **2370**. More specifically, the transfer axle **2388** can rotate within the opening **2347** of the axle portion **2346** such that a rotational motion can be transferred from one of the drive assemblies **2370** to the other drive assembly **2370**, as described in further detail herein.

The sidewalls **2342** each define a notch **2343** and include the spring protrusion **2344**. More specifically, the spring protrusions **2344** each extend in a substantially perpendicular direction from the sidewalls **2342**. As shown in FIGS. **13** and **14**, when the side members **2320** are coupled to the base **2340**, the notches **2322** of the side members **2320** each receive one of the spring protrusions **2344** of the base **2340**. Similarly, when the side members **2320** are coupled to the base **2340**, the notches **2343** defined by the base **2340** each receive a portion of one of the springs **2324**. In this manner, the spring rod **2323** and the spring **2324** of each side member **2320** are aligned with the spring protrusion **2344** extending from the side walls **2342** of the base **2340** such that the spring **2324** is placed in contact with a surface of the corresponding spring protrusion **2344**. With the side members **2320** movably coupled to the base **2340** (e.g., by disposing the mounting hardware in the slots **2325**), the spring **2324** of each side member **2320** can dampen a movement of the side member **2320** relative to the base **2340**. Similarly stated, the spring **2324** of each side member **2320** can engage the surface of the corresponding spring protrusion **2344** to exert a reaction force (e.g., brought on by a compression of the spring) in response to an external force (e.g., operational vibration, torque exerted by the motor, or the like) applied to one or both of the side members **2320**.

FIGS. **17-19** illustrate one of each of the leading support members **2350**, the trailing support members **2354**, and the transverse support members **2358**, respectively. As described above, the symmetry of the first drive assembly **2310** is such that the two leading support member **2350** are the same, the two trailing support members **2354** are the same, and the two transverse support members **2358** are the same. The leading support members **2350** are each fixedly coupled to one of the side members **2320**. As shown in FIG. **17**, the leading support members **2350** each define a lever arm notch **2355** that receives a lever arm **2391** of the secondary wheel assembly **2390**, a spring recess **2352** that receives a spring **2394** of the secondary wheel assembly **2390**, and a support track notch **2353** that receives, for example, a horizontal portion **2051** of the support track **2050** (see e.g., FIG. **23**).

The trailing support members **2354** are each fixedly coupled to one of the side members **2320** and are disposed in a rearward position relative to the leading support members **2354**. Expanding further, the trailing support members **2354** are spaced apart from the leading support members **2354** at a distance sufficiently large to allow a portion of the drive wheel assemblies **2370** to be disposed therebetween. As shown in FIG. **18**, the trailing support members **2354** each define a belt notch **2355** configured to receive a drive belt **2389** of the drive wheel assembly **2370** and a support track notch **2353** configured to receive the horizontal portion **2051** of the support track **2050** (e.g., as described with reference to the leading support member **2350**).

The transverse support members **2358** are each fixedly coupled to one of the leading support members **2350** and one of the trailing support members **2354**. Therefore, with the leading support members **2350** and the trailing support members **2354** each coupled to the corresponding side member **2320**, the transverse support member **2358** substantially encloses a space configured to house or receive a portion of the drive wheel assemblies **2370**. Furthermore, the arrangement of the support structure **2315** is such that a space defined between adjacent surfaces of the transverse support member **2358** is sufficiently large to receive, for example, a vertical portion **2052** of the support track **2050**.

As shown in FIG. **19**, the transverse support member **2358** defines a bearing opening **2359** that receives a support bearing **2377** of the drive wheel assemblies **2370**. More specifically, the support bearing **2377** is disposed within the bearing opening **2359** such that an outer surface of the support bearing **2377** forms a friction fit with a surface of the transverse support member **2358** that defines the bearing opening **2359**. Similarly stated, the outer surface of the support bearing **2377** and the surface of the transverse support member **2358** form a press fit to retain the support bearing **2377** within the bearing opening **2359**.

Referring back to FIGS. **13-15**, the first drive assembly **2310** includes four guide wheel assemblies **2360**. The guide wheel assemblies **2360** each include a mounting bracket **2361** and a guide wheel **2363**. More specifically, each of the guide wheels **2363** are rotatably coupled to one of the mounting brackets **2361** such that the guide wheels **2363** can rotate relative to the mounting brackets **2361**.

The guide wheel assemblies **2360** are each configured to be coupled to a portion of the support structure **2315**. Expanding further, as shown in FIGS. **13-16**, the mounting bracket **2361** of each guide wheel assembly **2360** is coupled to one of the leading support members **2350** or one of the trailing support members **2354**. Similarly stated, both of the leading support members **2350** are coupled to the mounting bracket **2361** included in one of the guide wheel assemblies **2360** and both of the trailing support members **2354** are coupled to the mounting bracket **2361** included in one of the guide wheel assemblies **2360**. The guide wheel assemblies **2360** are coupled to the support structure **2315** such that a portion of the guide wheel **2363** extends into the space defined between the transverse members **2358**. In this manner, the guide wheels **2363** can roll along a surface of the vertical portion **2052** of the support track **2050** when the first drive assembly **2310** is coupled thereto (see e.g., FIG. **23**).

As shown in FIGS. **13-15**, the guide wheel assemblies **2360** can be arranged relative to the support structure **2315** such that the guide wheels **2363** included in the guide wheel assemblies **2360** that are coupled to the leading support member **2350** are disposed substantially below the mounting bracket **2361**. Conversely, the guide wheels **2363** included in the guide wheel assemblies **2360** that are coupled to the trailing support member **2350** are disposed substantially above the mounting bracket **2361**. This arrangement can increase the surface area of the vertical portion **2051** of the support track **2050** that is in contact with at least one guide wheel **2360**. In this manner, a rotational motional about a

longitudinal centerline (not shown) of the support track **2050** can be minimized or eliminated. While shown in as being in a particular arrangement, in other embodiments, the guide wheels **2363** can be arranged in any suitable manner. For example, in some embodiments, all the guide wheels **2363** can be mounted below the mounting brackets **2361**. In other embodiments, all the guide wheels **2363** can be mounted above the mounting brackets **2361**. In still other embodiments, the guide wheels **2363** can be mounted to the mounting brackets **2361** in any combination of configurations (e.g., mounted above or below the mounting brackets **2361** in any suitable arrangement).

FIG. **20** is an exploded view of the drive wheel assembly **2370**. As described above, the symmetry of the first drive assembly **2310** is such that the drive wheel assemblies are the same. Thus, a discussion of the drive wheel assembly **2370** shown in FIG. **20** applies to both drive wheel assemblies **2370**. The drive wheel assembly **2370** includes a drive shaft **2371**, the drive bearing **2376**, the support bearing **2377**, a drive sprocket **2379**, a transfer sprocket **2381**, a drive wheel **2385**, the transfer axle **2388** (not shown in FIG. **20**), and a drive belt **2389**. The drive shaft **2371** has a first portion **2372**, a second portion **2373**, and a third portion **2374** and defines an opening **2375**. The first portion **2372** has a first diameter that is at least partially associated with the drive sprocket **2378**. Expanding further, the drive sprocket **2378** defines an opening **2380** that has a diameter that is associated with the diameter of the first portion **2372** of the drive shaft **2371**. In this manner, the drive sprocket **2378** is disposed about the first portion **2372** of the drive shaft **2371** such that a surface of the drive sprocket **2378** defining the opening **2380** forms a friction fit with an outer surface of the first portion **2372** of the drive shaft **2371**. Similarly, the drive bearing **2376** is disposed about the first portion **2372** such that an inner surface of the bearing forms a friction fit with the outer surface of the second portion **2372** of the drive shaft **2371**. Thus, a rotation of the drive shaft **2371** within the drive bearing **2376** rotates the drive sprocket **2378**. Moreover, with the drive bearing **2376** being retained with the bearing opening **2321** of one of the side member **2370**, the drive shaft **2371** can be rotated relative to the corresponding side member **2370**, as described in further detail herein.

The second portion **2373** of the drive shaft **2371** has a second diameter that is smaller than the diameter of the first portion **2372** and that is at least partially associated with the drive wheel **2385**. Expanding further, the drive wheel **2385** includes a hub **2386** that defines an opening **2387** with a diameter that is associated with the diameter of the second portion **2373** of the drive shaft **2371**. As shown in FIG. **20**, the opening **2387** of the drive wheel **2385** includes a keyway configured to receive a key that extends from an outer surface of the second portion **2373** of the drive shaft **2371**. In this manner, the drive wheel **2385** is fixedly disposed about the second portion **2373** of the drive shaft **2373**.

The third portion **2374** of the drive shaft **2371** has a third diameter that is smaller than the diameter of the second portion **2372** and that is at least partially associated with the support bearing **2377**. Expanding further, the support bearing **2377** is disposed about the third portion **2374** of the drive shaft **2371** such that an outer surface of the third portion **2374** forms a friction fit with an inner surface of the support bearing **2377**. Moreover, with the support bearing **2377** being disposed within the bearing opening **2359** of the transverse support member **2358**, the third portion **2374** of the drive shaft **2371** can be at least partially supported.

The opening **2375** defined by the drive shaft **2371** receives the output shaft **2312** of the motor **2311**. More specifically, the drive shaft **2371** can be fixedly coupled, at least temporarily, to the output shaft **2312** of the motor **2311**; thus, when the output shaft **2312** is rotated (e.g., in response to an activation signal from the electronic system **2700**), the drive shaft **2371** is concurrently rotated. With the drive bearing **2376** and the support bearing **2377** being disposed within the bearing opening **2321** of the side member **2320** and the bearing opening **2359** of the transverse support member **2358**, respectively, the drive shaft **2371** can rotate relative to the support structure **2315**. Moreover, the rotation of the drive shaft **2371** rotates both the drive sprocket **2378** and the drive wheel **2385**.

The drive sprocket **2378** is configured to engage the belt **2389**. More specifically, the drive sprocket **2389** includes a set of teeth **2379** that engage a set of teeth (not shown) that extend from an inner surface of the belt **2389**. The belt **2389** is further coupled the transfer sprocket **2381**. The transfer sprocket **2381** includes a set of teeth **2382** that engage the teeth of the belt **2389**. In this manner, the rotation of the drive sprocket **2378** (described above) rotates the belt **2389**, which, in turn, rotates the transfer sprocket **2381**. The transfer sprocket **2381** defines an opening **2383** configured to receive the transfer axle **2388** (see e.g., FIG. **16**). More specifically, the transfer axle **2388** can be fixedly coupled to the transfer sprockets **2381** of each drive wheel assembly **2370** such that a rotation of the transfer sprocket **2381** of the first drive wheel assembly **2370** (e.g., the drive wheel assembly **2370** coupled to the output shaft **2312** of the motor **2311**) rotates the transfer sprocket **2381** of the second drive wheel assembly **2370**. Thus, when the motor **2311** is activated to rotate the output shaft **2312**, both the drive wheels **2385** of both the drive wheel assemblies **2370** are urged to rotate.

In some embodiments, the side members **2320** and the base **2340** of the support structure **2315** can be arranged such that the spring **2324** of the side members **2320** is in a preloaded configuration (e.g., partially compressed without an additional external force being applied to one or both of the side members **2320**). More specifically, each spring **2324** can exert a force (e.g., due to the preload) on the surface of the corresponding spring protrusion **2344** of the base **2340** to place the corresponding side member **2320** in a desired position relative to the base **2340**. Moreover, with the drive bearings **2376** fixedly disposed within the bearing opening **2321** of the corresponding side members **2320** and with the transfer axle **2388** being disposed within the opening **2347** defined by the axle portion **2346** of the base **2340**, the belt **2379** disposed about the drive sprocket **2378** and the transfer sprocket **2381** can be placed in tension. Thus, the arrangement of the side members **2320** being movably coupled to the base **2340** can retain the belt **2379** in a suitable amount tension such that the belt **2379** does not substantially slip along the teeth **2379** of the drive sprocket **2378** and/or along the teeth **2382** of the transfer sprocket **2381**.

As shown in FIG. **21**, the first drive assembly **2310** includes the secondary wheel assembly **2390**. The secondary wheel assembly **2390** includes a lever arm **2391**, a secondary wheel **2393**, and a spring **2394**. The lever arm **2391** is a substantially angled member that includes an axle portion **2392**, a pivot portion **2395**, and an engagement portion **2396**. The axle portion **2392** is disposed at a first end of the lever arm **2391** and is movably coupled to the secondary wheel **2393** such that the secondary wheel **2393** rotates about the axle portion **2392**. The pivot portion **2395** is movably coupled to a portion of the leading support member

2350 that defines the lever arm notch 2351. For example, in some embodiments, the pivot portion 2395 of the lever arm 2391 can include an opening configured to receive, for example, a pivot pin (not shown) included in the leading support member 2350. In this manner, the pivot pin can define an axis about which the pivot portion 2395 can pivot or rotate.

The engagement portion 2396 is configured to engage a portion of the spring 2394. More specifically, as shown in FIG. 22, a first end portion of the spring 2394 is in contact with the spring recess 2352 defined by the leading support member 2350 and a second end portion of the spring 2394 is in contact with the engagement portion 2396. In this manner, the spring 2394 can exert a force on the engagement portion 2396 to pivot the lever arm 2391 about the pivot portion 2395. Expanding further, as shown in FIG. 22, the force exerted by the spring 2394 can pivot the lever arm 2391 such that the secondary wheel 2393 is pivoted towards the drive wheel 2385. Therefore, when the first drive assembly 2310 is disposed about the support track 2050, the secondary wheel 2393 can be placed in contact with a bottom surface of the horizontal portion 2051 of the support track 2050. Moreover, the force exerted by the spring 2394 can be such that the drive wheel 2385 and the secondary wheel 2393 exert a compressive force on a top surface and the bottom surface, respectively, of the horizontal portion 2051 of the support track 2051. This arrangement can, for example, increase the friction between the drive wheel 2385 and the horizontal portion 2051 of the support track 2050.

FIGS. 24-26 illustrate the second drive assembly 2400. The second drive assembly 2400 can function similarly to the first drive assembly 2310, thus, some portions of the second drive assembly 2400 are not described in further detail herein. The second drive assembly 2400 includes a support structure 2405, a set of guide wheel assemblies 2430, a set of primary wheel assemblies 2440, a coupler 2460, and an encoder 2470. As shown, at least a portion of the second drive assembly 2400 is substantially symmetrical about a longitudinal plane (not shown) defined by the second drive assembly 2400. In this manner, each side of the second drive assembly 2400 includes similar components, thereby increasing versatility and decreasing manufacturing costs. For example, while the second drive assembly 2400 is shown including two side members 2420 with the coupler 2460 and encoder 2470 being coupled to a particular side member 2420, in other embodiments, the coupler 2460 and encoder 2470 can be coupled to the other side member 2420.

The support structure 2405 includes two side members 2410, a base 2420, a set of leading support members 2431, a set of trailing support members 2432, and a set of transverse support members 2433. As shown in FIGS. 24-26, the side members 2410 are the same (e.g., due to the symmetry of the first drive assembly 2400). The side members 2410 each define a bearing opening 2411 that receives a bearing 2454 (FIG. 25) included in the drive wheel assembly 2470. More specifically, the bearing 2454 can be disposed within the bearing opening 2411 such that an outer surface of the drive bearing 2454 forms a friction fit with a surface of the side member 2410 that defines the bearing opening 2411. Similarly stated, the drive bearing 2454 and the surface of the side 2410 defining the bearing opening 2411 form a press fit to retain the drive bearing 2454 within the bearing opening 2411.

The base 2420 is configured to be fixedly coupled to the side members 2410. The base 2420 includes a mounting plate 2421 configured to extend from a top surface and from a bottom surface of the base 2420 to couple the second drive assembly 2400 to the base 2210 of the housing 2200 (e.g., via any suitable mounting hardware such as, for example, mechanical fasteners or the like). The arrangement of the mounting plate 2421 can be such that when the second drive assembly 2400 is disposed about the support track 2050, the mounting plate 2421 can substantially limit a movement of the second drive mechanism 2400 in transverse direction relative to the longitudinal centerline (not shown) of the support track 2050. In some embodiments, the mounting plate 2421 can include any suitable surface finish that can be sufficiently smooth to slide along a bottom surface of the horizontal portion 2051 of the support track 2050. In other embodiments, the mounting plate 2421 can be formed from a material such as, for example, nylon or the like that facilitates the sliding of the mounting plate 2421 along the bottom surface of the support track 2050.

The leading support members 2431, the trailing support members 2432, and the transverse support members 2433 can be arranged similar to the leading support members 2350, the trailing support members 2354, and the transverse support members 2358 described above with reference to FIGS. 17-19. In this manner, the side members 2410 and the support members 2431, 2432, and 2433 can define a space configured to substantially enclose at least a portion of the primary wheel assemblies 2440. Moreover, the transverse support members 2433 can define an opening configured to receive a bearing 2454 of the primary wheel assembly 2350 in a similar manner as the transverse member 2333 described above. As shown in FIGS. 24-26, the leading support members 2431, the trailing support members 2432, and the transverse support members 2433 can differ, however, in that the leading support members 2431, the trailing support members 2432, and the transverse support members 2433 need not include one or more notches and/or recesses to accommodate any portion of the second drive assembly 2400.

The second drive assembly 2400 includes four guide wheel assemblies 2440. The guide wheel assemblies 2440 each include a mounting bracket 2441 and a guide wheel 2443. More specifically, each of the guide wheels 2443 are rotatably coupled to one of the mounting brackets 2441 such that the guide wheels 2443 can rotate relative to the mounting brackets 2441. The guide wheel assemblies 2440 are each configured to be coupled to a portion of the support structure 2405. Expanding further, as shown in FIGS. 24-26, the mounting bracket 2441 of each guide wheel assembly 2440 is coupled to one of the leading support members 2431 or one of the trailing support members 2432. Similarly stated, both of the leading support members 2431 are coupled to the mounting bracket 2441 included in one of the guide wheel assemblies 2440 and both of the trailing support members 2432 are coupled to the mounting bracket 2441 included in one of the guide wheel assemblies 2440. The guide wheel assemblies 2440 are coupled to the support structure 2405 such that a portion of the guide wheel 2443 extends into the space defined between the transverse members 2433. In this manner, the guide wheels 2443 can roll along a surface of the vertical portion 2052 of the support track 2050 when the second drive assembly 2400 is coupled thereto (see e.g., FIG. 26). As described above with reference to the first drive assembly 2310, the guide wheel assemblies 2440 can be arranged in any suitable configuration to limit a rotational movement of the second drive assembly 2400 about the longitudinal centerline of the support track 2050.

The primary wheel assemblies 2450 each include a primary wheel 2451 having a hub 2452 and an axle 2453, and

the bearings **2454**. As described above, the axle **2453** can be disposed within the bearings **2354** while the bearings **2354** are coupled to the side members **2410** and the transverse members **2433**. In this manner, each primary wheel **2451** can rotate about the corresponding axle **2453** relative to the support structure **2405**. As shown in FIG. **26**, the second drive assembly **2400** is disposed about the support track **2050** such that the primary wheels **2451** roll along the top surface of the horizontal portion **2051**. Similarly, the guide wheels **2443** roll along a surface of the vertical portion **2052** of the support track **2050**.

As shown in FIGS. **24** and **26**, the axle **2453** is configured to extend through the bearing **2454** disposed within the opening **2411** of the side members **2410**. In this manner, the coupler **2460** can couple to the axle **2453** to couple the axle **2453** to the encoder **2470**. Thus, the encoder **2470** can receive and/or determine information associated with the rotation of the primary wheel **2451**. For example, the encoder **2470** can determine position, rotational velocity, rotational acceleration, or the like. Furthermore, the encoder **2470** can be in electrical communication (e.g., via a wired communication or a wireless communication) with a portion of the electronic system **2700** and can send information associated with the second drive assembly **2400** to the portion of the electronic system **2700**. Upon receiving the information from the encoder **2470**, a portion of the electronic system **2700** can send a signal to any other suitable system associated with performing an action (e.g., increasing or decreasing the power of one or more motors or the like), as described in further detail herein. In some instances, the electronic system **2700** can determine the position of the trolley **2100** relative to the support track **2050** based at least in part on the information sent from the encoder **2470** associated with the second drive assembly **2400**. In such instances, a user (e.g., doctor, physician, nurse, technician, or the like) can input a set of parameters associated with a portion of the support track **2050** along which the trolley **2100** moves. In this manner, the user can define a desired path along the support track **2050** for a therapy session.

FIGS. **27-33** illustrate the support mechanism **2500** included in the trolley **2100**. As shown in FIG. **27**, the support mechanism **2500** includes a tether **2505**, a winch assembly **2510**, a guide mechanism **2540**, a first pulley **2563**, a second pulley **2565**, and a cam mechanism **2570**. The tether **2505** can be, for example, a rope or other long flexible member that can be formed from any suitable material such as nylon or other suitable polymer. The tether **2505** includes a first end portion **2506** that is coupled to a portion of the winch assembly **2510** and a second end portion **2507** that can be coupled to any suitable patient attachment mechanism such as, for example, the patient attachment mechanism **2800** shown in FIG. **34**. The tether **2505** is configured to engage a portion of the winch assembly **2510**, the guide mechanism **2540**, the cam mechanism **2570**, the first pulley **2563**, and the second pulley **2565** such that the support mechanism **2500** actively supports at least a portion of the body weight of a patient, as described in further detail herein.

As shown in FIGS. **29** and **30**, the winch assembly **2510** includes a motor **2511**, a mounting flange **2515**, a coupler **2520**, a drum **2525**, and encoder assembly **5230**. The motor **2511** is coupled to the coupler **2520** and is in electrical communication with a portion of the electronic system **2700**. The motor **2511** includes an output shaft **2512** that engages an input portion (not shown) of the coupler **2520** such that rotation of the output shaft **2512** of the motor **2511** rotates an output member **2521** of the coupler **2520**. More specifically, the motor **2511** receives an activation signal (e.g., a flow of electrical current) from the electronic system **2700** to cause the motor **2511** to rotate the output shaft **2512** in a first rotational direction or in a second rotational direction, opposite the first rotational direction. The output shaft **2512**, in turn, rotates the output member **2521** of the coupler **2520** in the first rotational direction or the second rotational direction, respectively.

The mounting flange **2515** is disposed about a portion of the coupler **2520** and includes a portion that can be coupled to the third side member **2250** of the housing **2200**. In this manner, the motor **2511** is supported by the mounting flange **2515** and the housing **2200**. The output member **2521** of the coupler **2520** is coupled to a mounting plate **2522** of the drum **2525** such that when the output shaft **2512** of the motor **2511** is rotated in the first direction or the second direction, the drum **2525** is rotated in first direction or the second direction, respectively. While not shown, in some embodiments, the coupler **2520** can include one or more gears that can be arranged in any suitable manner to define a desirable gear ratio. In this manner, the rotation of the output shaft **2512** can be in the first direction or the second direction with a first rotational velocity and the rotation of the drum **2525** can be in the first direction or the second direction, respectively, with a second rotational velocity that is different from the first rotational velocity of the output shaft **2525** (e.g., a greater or lesser rotational velocity). In some embodiments, the coupler **2520** can include one or more clutches that can be configured to reduce and/or dampen an impulse (i.e., a force) that can result from the electronic system **2700** sending a signal to the motor **2511** that is associated with changing the rotational direction of the output shaft **2512**.

The drum **2525** is disposed between the mounting plate **2522** and an end plate **2529**. As described in further detail herein, an encoder drum **2531** of the encoder assembly **2530** is coupled to the end flange **2529** such that a least a portion of the encoder assembly **2530** is disposed within an inner volume **2528** defined by the drum **2525**. The drum **2525** has an outer surface **2526** that defines a set of helical grooves **2527**. The helical grooves **2527** receive a portion of the tether **2505** and define a path along which the tether **2505** can wrap to coil and/or uncoil around the drum **2525**. For example, the motor **2511** can receive a signal from the electronic system **2700** to rotate the output shaft **2512** in the first direction. In this manner, the drum **2525** is rotated in the first direction and the tether **2505** can be, for example, coiled around the drum **2525**. Conversely, the motor **2511** can receive a signal from the electronic system **2700** to rotate the output shaft **2512** in the second direction, thus, the drum is rotated in the second direction and the tether **2505** can be, for example, uncoiled from the drum **2525**.

The encoder assembly **2530** includes the encoder drum **2531**, a mounting flange **2532**, a bearing bracket **2533**, a bearing **2535**, a coupler **2536**, an encoder **2537**, and an encoder housing **2538**. As described above, a first end portion of the encoder drum **2531** is coupled to the end flange **2529** of the drum **2525** such that a portion of the encoder assembly **2530** is disposed within the inner volume **2528** of the drum **2525**. The mounting flange **2532** is coupled to a second end portion of the encoder drum **2531** and is further coupled to the bearing bracket **2533**. The bearing bracket **2533** includes an axle **2534** about which the bearing **2535** is disposed. The coupler **2536** is coupled to the axle **2534** of the bearing bracket **2533** and is configured to couple the encoder **2537** to the bearing bracket **2533**. As shown in FIG. **28**, the coupler **2536** and the encoder **2537** are disposed within the encoder housing **2538**. More specifi-

cally, the coupler **2536** is movably disposed within the encoder housing **2538** and the encoder **2537** is fixedly coupled to the encoder housing **2538**. Moreover, a first end portion of the encoder housing **2538** is disposed about the bearing **2535** and a second end portion of the encoder housing **2538** is in contact with and fixedly coupled to the recessed portion **2244** of the second side member **2240** of the housing **2240**. In this manner, the encoder drum **2531**, the mounting flange **2532**, the bearing bracket **2533**, and the coupler **2536** are configured to rotate concurrently with the drum **2525**, relative to the encoder **2537** and the encoder housing **2538**. Thus, the encoder **2537** can receive and/or determine information associated with the rotation of the drum **2525**. For example, the encoder **2537** can determine position, rotational velocity, rotational acceleration, feed rate of the tether **2505**, or the like. Furthermore, the encoder **2537** can be in electrical communication (e.g., via a wired communication or a wireless communication) with a portion of the electronic system **2700** and can send information associated with the winch assembly **2510** to the portion of the electronic system **2700**. Upon receiving the information from the encoder **2537**, a portion of the electronic system **2700** can send a signal to any other suitable system associated with performing an action (e.g., increasing or decreasing the power of one or more motors or the like), as described in further detail herein.

Referring back to FIG. **27**, the guide mechanism **2540** of the support mechanism **2500** is at least partially disposed within the guide mechanism opening **2215** of the base **2210** included in the housing **2200**. More specifically, the guide mechanism **2540** includes a set of mounting brackets **2541** that are coupled to the mounting tabs **2216** of the base **2210**. In this manner, at least a portion of the guide mechanism **2540** is suspended within the guide mechanism opening **2215**. As shown in FIG. **31**, the guide mechanism **2540** includes the mounting brackets **2541**, a guide drum assembly **2545**, a stopper bracket **2550**, a stopper **2551**, a roller assembly **2554**, a coupler **2559**, a support bracket **2560**, and an encoder **2561**. As described above, the mounting brackets **2541** are coupled to the mounting tabs **2216** of the base **2210**. The mounting brackets **2541** each include a first mounting portion **2542** that is movably coupled to a portion of the guide drum assembly **2545**, a second mounting portion **2543** that is fixedly coupled to the stopper bracket **2550**, and a pivot portion **2544** that is movably coupled to a portion of the roller assembly **2554**. The stopper bracket **2550** is further coupled to the stopper **2551** and is configured to limit a movement of the guide drum assembly **2545** relative to the mounting brackets **2541**.

The guide drum assembly **2545** includes a guide drum **2546**, a set of pivot plates **2547**, and a stopper plate **2549**. The guide drum **2546** is movably coupled to the pivot plates **2547**. For example, while not shown in FIG. **31**, the pivot plates **2547** can each include an opening configured to receive an axle about which the guide drum **2546** can rotate. The pivot plates **2547** each include a pivot axle **2548** that can be disposed within an opening (not shown) defined by the first mounting portion **2542** of the mounting brackets **2541**. In this manner, the guide drum assembly **2545** can pivot about the pivot axles **2548** relative to the mounting brackets **2541**. The stopper plate **2549** is coupled to the pivot plates **2547** and is configured to engage a portion of the stopper **2551** to limit the pivoting motion of the guide drum assembly **2545** relative to the mounting brackets **2541**. More specifically, with the stopper bracket **2550** fixedly coupled to the mounting brackets **2541** and to the stopper **2551**, the guide drum assembly **2545** can pivot toward the stopper bracket **2550** (e.g., in response to a force exerted on tether **2505**, as described in further detail herein) such that the stopper plate **2549** is placed in contact with the stopper **2551**. The stopper **2551** can be any suitable shape, size, or configuration. For example, in some embodiments, the stopper **2551** can be an elastomeric member configured to absorb a portion of a force exerted by the guide drum assembly **2545** when the stopper plate **2549** is placed in contact with the stopper **2551**.

The roller assembly **2554** includes a set of swing arms **2555** and a set of rollers **2558**. The swing arms **2555** include a first end portion **2556** and a second end portion **2557**. The first end portion **2556** of the swing arms **2555** are movably coupled to the rollers **2558**. More specifically, the rollers **2558** can be arranged such that a spaced defined between the rollers **2558** can receive a portion of the tether **2505**. Thus, when the tether **2505** is moved relative to the rollers **2558**, the rollers **2558** can rotate relative to the swing arms **2555**. The second end portion **2557** of the swing arms **2555** are coupled to the pivot portion **2543** of the mounting brackets **2541**. For example, as shown in FIG. **31**, the pivot portion **2543** can include a set of axles disposed within a bearing. In this manner, the second end portion **2557** of the swing arms **2555** can couple to the axles such that the roller assembly **2554** and the axles can pivot relative to the mounting brackets **2541** (e.g., in response to a force exerted on tether **2505**, as described in further detail herein).

The coupler **2559** included in the guide mechanism **2540** is coupled to the axle of the pivot portion **2543** of one of the mounting brackets **2541**. The coupler **2559** is further coupled to an input shaft of the encoder **2561**. More specifically, the support bracket **2560** is coupled to the base **2210** of the housing **2200** and is also coupled to a portion of the encoder **2561** to limit the movement of a portion of the encoder **2561** relative to the base **2210**. Thus, the encoder **2561** can receive and/or determine information associated with the pivoting motion of the roller assembly **2554** relative to the mounting brackets **2541**. For example, the encoder **2561** can determine position, rotational velocity, rotational acceleration, feed rate of the tether **2505**, or the like. Furthermore, the encoder **2561** can be in electrical communication (e.g., via a wired communication or a wireless communication) with a portion of the electronic system **2700** and can send information associated with the guide mechanism **2540** to the portion of the electronic system **2700**. Upon receiving the information from the encoder **2561**, a portion of the electronic system **2700** can send a signal to any other suitable system associated with performing an action (e.g., increasing or decreasing the power of one or more motors **2311** and **2511**, changing the direction of one or more of the motors **2311** and **2511**, or the like).

As shown in FIG. **32**, the first pulley **2563** and the second pulley **2565** are rotatably coupled to a first pulley bracket **2564** and a second pulley bracket **2565**, respectively. The first pulley bracket **2564** and the second pulley bracket **2565** are further coupled to the base **2210** of the housing **2200**. In this manner, the first pulley **2563**, the second pulley **2565**, and at least a portion of the cam mechanism **2570** can be engage the tether **2505** to provide a mechanical advantage to the winch assembly **2510**, as described in further detail herein.

As shown in FIGS. **32** and **33**, the cam mechanism **2570** includes a cam pulley assembly **2571**, a cam **2580**, a coupler **2585**, a coupler housing **2586**, an encoder **2587**, and a bias mechanism **2588**. The cam pulley assembly **2571** includes a cam pulley **2572**, a cam arm **2574**, a cam axle **2575**, and a spacer **2576**. The cam arm **2574** includes a first end portion

that is rotatably coupled to the cam pulley **2572** and a second end portion that is rotatably coupled to the cam axle **2575**. The cam axle **2575** extends through the cam pivot opening **2220** (defined by the base **2210**), the spacer **2576**, and the cam **2580** to be coupled to the coupler **2585**. The spacer **2576** is coupled to the base **2210** and is disposed between the second side **2212** of the base **2210** and a surface of the cam **2580**. The spacer **2576** can be formed from a material having a relatively low friction coefficient such as, for example, polyethylene, nylon, or the like to allow the cam **2580** to move relatively easily along a surface of the spacer **2576**. In this manner, the cam **2580** is spaced a sufficient distance from the second side **2212** of the base **2210** to allow a portion of the bias mechanism **2588** to be disposed therebetween, as described in further detail herein.

The cam **2580** of the cam assembly **2570** defines an opening **2581**, and includes a mounting portion **2582** and an engagement surface **2583**. The engagement surface **2583** of the cam **2580** is in contact with a portion of the bias mechanism **2588**, as described in further detail herein. The opening **2581** defined by the cam **2580** receives a bearing **2584**. When disposed within the opening **2581**, the bearing **2584** allows the cam **2580** to rotate about the cam axle **2575**. The mounting portion **2582** of the cam **2580** is at least partially disposed within the cam pulley opening **2219** and is coupled to the cam pulley **2572**. For example, as shown in FIG. **33**, the mounting portion **2582** is a threaded rod extending from a surface of the cam **2580** that can be received by a threaded opening (not shown) defined by the cam pulley **2572**. In this manner, movement of the cam pulley assembly **2571**, in response to a change in force exerted on the tether **2505** (e.g., an increase or a decrease of force), rotates the cam **2580** about the cam axle **2575** (as described above).

The coupler housing **2586** is coupled to a surface of the cam **2580** that is opposite the side adjacent to the spacer **2576**. In other words, the coupler housing **2586** extends away from the base **2210** when coupled to the cam **2580**. The coupler housing **2586** is further coupled to the encoder **2587**. Thus, when the cam **2580** is rotated about the cam axle **2575**, the coupler housing **2586** and the encoder **2587** are also rotated about the cam axle **2575**. The coupler **2585** is disposed within the coupler housing **2586** and is coupled to both the cam axle **2575** and an input portion (not shown) of the encoder **2575**. Therefore, with the coupler **2585** coupled the to the cam axle **2575** and the input portion of the encoder **2587**, the rotation of the cam **2580** and the coupler housing **2586** rotates the encoder **2587** about its input portion. In this manner, the encoder **2587** can receive and/or determine information associated with the pivoting motion of the cam **2580** and/or the cam pulley assembly **2571** relative to the cam axle **2575**. For example, the encoder **2587** can determine position, rotational velocity, rotational acceleration, feed rate of the tether **2505**, or the like. Furthermore, the encoder **2587** can be in electrical communication (e.g., via a wired communication or a wireless communication) with a portion of the electronic system **2700** and can send information associated with the cam mechanism **2570** to the portion of the electronic system **2700**. Upon receiving the information from the encoder **2587**, a portion of the electronic system **2700** can send a signal to any other suitable system associated with performing an action (e.g., increasing or decreasing the power of one or more motors **2311** and **2511**, changing the direction of one or more of the motors **2311** and **2511**, or the like).

The bias mechanism **2588** includes an axle **2589**, a mounting flange **2590**, a first pivot arm **2591**, a second pivot arm **2595**, a guide member **2596**, a bias member **2597**, and a mounting post **2598**. The axle **2589** is movably disposed within the mounting flange **2588** and is configured to extend through the bias mechanism opening **2217** defined by the base **2210** to be fixedly disposed within an axle opening **2592** defined by the second pivot arm **2591**. Expanding further, a portion of the mounting flange **2589** extends through the bias mechanism opening **2217** and beyond the second side **2212** of the base **2210** to be in contact with a surface of the second pivot arm **2591**. In this manner, the surface of the second pivot arm **2591** is offset from the second side **2212** of the base **2210**. Moreover, the arrangement of the spacer **2576** (described above) is such that when the axle **2589** is disposed within the axle opening **2592**, a second surface of the first pivot arm **2591** is offset from a surface of the cam **2580**. Thus, the first pivot arm **2591** can pivot relative to the base **2210** with a relatively low amount of friction. In some embodiments, at least the portion of the mounting flange **2590** that extends through the bias mechanism opening **2217** can be made from a material having a relatively low coefficient of friction such as, for example, polyethylene, nylon, or the like.

The first pivot arm **2591** defines the axle opening **2592** and a guide member opening **2593**, and includes an engagement member **2594**. The guide member opening **2593** is configured to receive a portion of the guide member **2596** to couple the guide member **2596** to the first pivot arm **2591**. The guide member **2596** extends from a surface of the first pivot arm **2591** toward the base **2210** such that a portion of the guide member **2596** extends through the guide member opening **2218** defined by the base **2210**. In some embodiments, the guide member **2596** can include a sleeve or the like configured to engage the base **2210**. In such embodiments, the sleeve can be formed from a material having a relatively low friction coefficient such as, for example, polyethylene, nylon, or the like. Thus, the guide member **2596** can move within the guide member track **2218** when the first pivot arm **2591** is moved relative to the base **2210**.

The engagement member **2594** of the first pivot arm **2591** extends from a surface of the first pivot arm **2591** toward the cam **2580**. In this manner, the engagement member **2594** can be moved along the engagement surface **2583** of the cam **2580** when the cam **2580** is moved relative to the base **2210**, as described in further detail herein. In some embodiments, the engagement member **2594** can be rotatably coupled to the first pivot arm **2591** and can be configured to roll along the engagement surface **2583**. In other embodiments, the engagement member **2594** and/or the engagement surface **2583** can be formed from a material having a relatively low friction coefficient. In such embodiments, the engagement member **2594** can be slid along the engagement surface **2583**.

The second pivot arm **2595** of the bias mechanism **2588** has a first end portion that is fixedly coupled to the axle **2589** and a second end portion that is coupled to a first end portion of the bias member **2597**. The mounting post **2598** is fixedly coupled to the base **2210** and is further coupled to a second end portion of the bias member **2597**. Therefore, the second pivot arm **2595** can pivot relative to the mounting flange **2590** between a first position, where the bias member **2597** is in a first configuration (undeformed configuration), and a second position, where the bias member **2597** is in a second configuration (deformed configuration). For example, in some embodiments, the bias member **2597** can be a spring that can be moved between an uncompressed configuration (e.g., the first configuration) and a compressed configuration (e.g., the second configuration). In other embodiments, the

bias member **2597** can be a spring that can be moved between an unexpanded and an expanded configuration. In other words, the bias member **2597** can be either a compression spring or an expansion spring, respectively. In still other embodiments, the bias member **2597** can be any other suitable biasing mechanism and/or energy storage device such as, for example, a gas strut or the like.

When the cam **2580** is rotated from a first position to a second position in response to a force exerted on the tether **2505** (as described above), the bias member **2597** can exert a reaction force that resists the rotation of the cam **2580**. More specifically, with the engagement member **2594** in contact with the engagement surface **2583** of the cam **2580**, the bias member **2587** exerts the reaction force that resists the movement of the engagement member **2594** along the engagement surface **2583**. Therefore, in some instances, relatively small changes in the force exerted on the tether **2505** may not be sufficiently large to rotate the cam **2580** and the cam pulley assembly **2571**. This arrangement can reduce undesirable changes in the amount of body weight supported by the support system **2000** in response to minor fluctuations of force exerted on the tether **2505**.

FIG. **34** illustrates the patient attachment mechanism **2800**. The patient attachment mechanism **2800** can be mated with the second end portion **2507** of the tether **2505** to couple the patient attachment mechanism **2800** to the trolley **2100**. Moreover, the patient attachment mechanism **2800** can be coupled to a harness or the like, worn by the patient, to couple the patient to the support system **2000**, as described below.

The patient attachment mechanism **2800** has a first coupling portion **2810** and a second coupling portion **2812**. The first coupling portion **2810** includes a coupling mechanism **2811** configured to couple to the second end portion **2507** of the tether, as described above. For example, the coupling mechanism **2811** can be a loop or hook configured to couple to an attachment device of the tether **2505** (not shown in FIGS. **2-34**). The second coupling portion **2821** is movably coupled to a first arm **2820** and a second arm **2840**. As described in further detail herein, the first **2820** and the second arm **2840** can pivot relative to each other to absorb at least a portion of a force exerted by the weight of a patient coupled to the patient attachment mechanism **2800**.

The first arm **2820** of the patient attachment mechanism **2800** includes a pivot portion **2821** and a mount portion **2822**. The pivot portion **2821** is movably coupled to the second coupling portion **2812**. The mount portion **2822** receives a guide rod **2830**, as described in further detail herein. The first arm **2820** defines a slot **2824** that receives a portion of the second arm **2840** and an opening **2826** that receives a portion of a harness worn by the patient.

The second arm **2840** has a pivot portion **2841** and a coupling portion **2842**. The pivot portion **2841** is movably coupled to the second coupling portion **2812**. In this manner, both the first arm **2820** and the second arm **2840** can pivot relative to the coupling portion **2812** and relative to each other, as described in further detail herein. The coupling portion **2842** defines an opening **2843** that receives a portion of the harness worn by the patient. The coupling portion **2842** is also movably coupled to a first end portion of a first energy storage member **2844** and a first end portion of a second energy storage member **2851** (collectively referred to as energy storage member **2850**). The energy storage members **2850** can be, for example, gas struts or the like.

As shown in FIG. **34**, the energy storage members **2850** are configured to extend towards the first arm **2820**. More specifically, the second energy storage member **2851** includes a coupling portion **2852** that is movably coupled to the guide rod **2830** of the first arm **2820**. The first energy storage member **2844** also includes a coupling portion (not shown in FIG. **34**) that is movably coupled to an engagement member **2845** and further coupled to the coupling portion **2852** of the second energy storage member **2851**. Similarly stated, the coupling portion of the first energy storage member **2844** extends in a substantially perpendicular direction relative to a longitudinal centerline (not shown) of the first energy storage member **2844**.

The engagement member **2845** is movably coupled to the coupling portion of the first energy storage member **2844** and the coupling portion **2852** of the second coupling portion **2851**. The engagement member **2845** is configured to be placed in contact with an engagement surface **2825** of the first arm **2820** that at least partially defines the slot **2825**. Similarly stated, the engagement member **2845** is disposed within the slot **2824** defined by the first arm **2820** and in contact **2825** with the engagement surface **2825**. Moreover, the arrangement of the engagement member **2845** and the energy storage members **2850** allows the engagement member **2845** to roll along the engagement surface **2825**.

When a force is exerted on the first arm **2820** the second arm **2840** by the patient, the first arm **2820** and the second arm **2840** pivot about the second coupling portion **2812** towards one another. The pivoting of the first arm **2820** and the second arm **2840** moves the engagement member **2845** along the engagement surface **2825** and further moves the energy storage members **2850** for a configuration of lower potential energy to a configuration of higher potential energy (e.g., compresses a gas strut). Thus, the energy storage members **2850** can absorb at least a portion of a force exerted of the patient attachment mechanism **2800**. Moreover, when the force exerted on the patient attachment mechanism **2800** is less than the potential energy of the energy storage members **2850** in the second configuration, the energy storage members **2850** can move towards their first position to pivot the first arm **2820** and the second arm **2840** away from one another.

In use, the patient support system **2000** can be used to actively support at least a portion of the body weight of a patient that is coupled thereto. For example, in some instances, a patient is coupled to the patient attachment mechanism **2800**, which, in turn, is coupled to the second end portion **2507** of the tether **2505**, as described above. In this manner, the support system **2000** (e.g., the tether **2505**, the trolley **2100**, and the support rail **2050**) can support at least a portion of the body weight of the patient.

In some instances, a user (e.g., a technician, a therapist, a doctor, a physician, or the like) can input a set of system parameters associated with the patient and the support system **2000**. For example, in some embodiments, the user can input a set of system parameters via a remote control device such as, for example, a personal computer, a mobile device, a smart phone, or the like. In other embodiments, the user can input system parameters on, for example, a control panel included in or on the trolley **2100**. The system parameters can include, for example, the body weight of the patient, the height of the patient, a desired amount of body weight to be supported by the support system **2000**, a desired speed of the patient walking during gait therapy, a desired path or distance along the length of the support track **2050**, or the like.

With the system parameters entered, the patient can begin, for example, a gait therapy session. In some instances, the trolley **2100** can move along the support structure **2050** (as described above with reference to FIGS. **23** and **26**) in

response to the movement of the patient. Similarly stated, the trolley **2100** can move along the support structure **2050** as the patient walks. In some instances, the trolley **2100** can be configured to remain substantially over-head of the patient. In such instances, the electronic system **2700** can execute a set of instructions associated with controlling the motor **2311** of the drive system **2300** based on information received from, for example, the encoder **2470** of the drive system **2300**, the encoder **2561** of the guide mechanism **2540**, and/or the encoder **2587** of the cam assembly **2570**. For example, the electronic system **2700** can send a signal to the motor **2311** of the drive system **2300** operative in changing the rotational velocity of the drive wheels **2385** based at least in part on information associated with the encoder **2561** of the guide mechanism **2540**. Expanding further, in some instances, the patient may walk faster than the trolley **2100**, thereby changing the angle of the tether **2505** and the guide mechanism **2540** relative to the base **2210**. Thus, the encoder **2561** of the guide mechanism **2540** can send a signal associated with the angle of the guide mechanism **2540** relative to the base **2210** and upon receiving the signal, the electronic system **2700** can send a signal to the motor **2311** of the drive system **2300** to increase the rotational velocity of the drive wheels **2385**. In this manner, the position of the trolley **2100** relative to the patient can be actively controlled based at least in part on a user defined parameter and further based at least in part on information received from the encoder **2470** of the drive system **2300**, the encoder **2561** of the guide mechanism **2540**, and/or the encoder **2587** of the cam assembly **2570**. Although described as being actively controlled to be over-head of the patient, in other instances, the user can define a parameter associated with the trolley **2100** trailing the patient by a desired distance or leading the patient by a desired distance.

In some instances, the amount of force exerted on the tether **2505** by the patient may increase or decrease. By way of example, a patient may stumble, thereby increasing the amount of force exerted on the tether **2505**. In such instances, the increase of force exerted on the tether **2505** can pivot the guide mechanism **2540** and can move the cam pivot arm **2571** in response to the increase in force. The movement of the cam pivot arm **2571** moves the cam assembly **2570** (as described above with reference to FIG. **33**). In this manner, the encoder **2561** of the guide mechanism **2540** and the encoder **2587** of the cam assembly **2570** can send a signal to the electronic system **2700** associated with the changes in the state of the guide mechanism **2540** and the cam assembly **2570**, respectively.

Upon receiving the signals from the encoders **2561** and **2587**, the processor can execute a set of instructions included in the memory associated the cam assembly **2570**. For example, the processor can determine the position of the cam **2580** or the guide mechanism **2540**, the velocity and the acceleration of the cam **2580** or the guide mechanism **2540**, or the like. Based on the determining of the changes in the guide mechanism **2540** and the cam assembly **2570** configurations, the processor can send a signal to the motor **2311** of the first drive assembly **2310** and/or the motor **2511** of the winch assembly **2510** to change the current state of the drive system **2300** and/or the patient support mechanism **2500**. In some instances, the magnitude of change in the state of the drive system and/or the patient support mechanism **2500** is based at least in part on a proportional-integral-derivative (PID) control. In such instances, the electronic system **2700** (e.g., the processor or any other electronic device in communication with the processor) can determine the changes of the patient support mechanism **2500** and model the changes based on the PID control. Based on the result of the modeling the processor can determine the suitable magnitude of change in the drive system **2300** and/or the patient support mechanism **2500**.

After a relatively short time period (e.g., much less than a second, for example, after one or a few clock cycles of the processor) the processor can receive a signal from the encoder **2470** of the drive system **2300**, the encoder **2537** of the winch assembly **2510**, the encoder **2561** of the guide mechanism **2540**, and/or the encoder **2587** of the cam assembly **2570** associated with a change in configuration of the drive system **2300**, the winch assembly **2510**, the guide mechanism **2540**, and/or the cam assembly **2570**, respectively. In this manner, one or more of the electronic devices included in the electronic system **2700**, including but not limited to the processor, execute a set of instructions stored in the memory associated with the feedback associated with the encoders **2470**, **2537**, **2561**, and **2587**. Thus, the drive system **2300** and the patient support mechanism **2500** of the trolley **2100** can be actively controlled in response to a change in force exerted on the tether **2505** and based at least in part on the current and/or previous states of the drive system **2300** and the patient support system **2500**. Similarly stated, the support system **2000** can actively reduce the amount a patient falls after stumbling or falling for other reasons.

While the patient support system **2000** is described above with reference to FIGS. **2-34** as actively supporting a portion of the body weight of the patient, in some embodiments, a patient support system can passively (i.e., not actively) support a portion of the body weight of a patient. For example, FIGS. **35** and **36** illustrate a body weight support system **3900** according to an embodiment. The body weight support system **3900** (also referred to herein as "support system") can be used to support a portion of a patient's body weight, for example, during gait therapy, gait training, or the like. The support system **3900** can be movably coupled to a support track (not shown) that is configured to support the weight of the support system **3900** and the weight of the patient utilizing the support system **3900**. The support track can be, for example, similar to or the same as the support track **2050** described above.

The support system **3900** includes a first coupling portion **3910** and a second coupling portion **3940**. The first coupling portion **3910** is configured to movably couple to the support track, as described above. The first coupling portion **3910** includes a first side assembly **3911**, a second side assembly **3921**, and a base **3930**. The first side assembly **3911** includes a set of drive wheels **3912**, a set of guide wheels **3913**, an outer wall **3914**, an inner wall **3915**, and a set of couplers **3916**. The couplers **3916** are configured to extend between the outer wall **3914** and the inner wall **3915** to couple the outer wall **3914** and the inner wall **3915** together. The outer wall **3914** is further coupled to the base **3930**. The drive wheels **3912** are arranged into an upper set of drive wheels **3912** configured to be disposed on a top surface of the support track, and a lower set of drive wheels **3912** configured to be disposed on a bottom surface of the support track. In this manner, the drive wheels **3912** roll along a horizontal portion of the support track (not shown in FIGS. **35** and **36**). The guide wheels **3913** are arranged in a perpendicular orientation relative to the drive wheels **3912** and are configured to roll along a vertical portion of the support track (e.g., as similarly described above with reference to FIG. **23**.

The second side assembly **3921** includes a set of drive wheels **3922**, a set of guide wheels **3923**, an outer wall **3924**, an inner wall **3925**, and a set of couplers **3916**. The first side

assembly **3911** and the second side assembly **3921** are substantially the same and arranged in a mirrored configuration. Therefore, the second side assembly **3921** is not described in further detail herein and should be considered the same as the first side assembly **3921** unless explicitly described.

As shown in FIG. **36**, the second coupling portion **3940** includes a cylinder **3941**, an attachment member **3945**, a piston **3950**, and an energy storage member **3960**. The cylinder **3941** is coupled to the base **3930** and is configured to house the spring **3960** and at least a portion of the piston **3950**. More specifically, the cylinder **3941** defines an opening **3942** at an end portion, opposite the base **3930**, through which at least a first end portion **3951** of the piston **3950** can move. The piston **3950** further has a second end portion **3952** that is in contact with a portion of the energy storage member **3960**. The energy storage member **3960** can be any suitable device configured to move between a first configuration having lower potential energy and a second configuration having a higher potential energy. For example, as shown in FIG. **36**, the energy storage member **3960** can be a spring that is compressed when moved to its second configuration.

The attachment mechanism **3945** includes a first coupling portion **3946** that is coupled to the first end portion **3951** of the piston **3950**, and a second coupling portion **3947** that can be coupled to, for example, a harness worn by a patient. As shown in FIGS. **35** and **36**, the second end portion **3952** can be an annular protrusion. In this manner, a portion of the harness such as a hook or the like can be at least partially disposed within the opening defined by the second coupling portion **3947** to couple the patient to the support system **3900**.

In use, the patient can be coupled to the support system **3900** (as described above) such that the support system **3900** supports at least a portion of the body weight of the patient. In this manner, the patient can walk along a path associated with the support track (not shown). With the support system **3900** coupled to the patient, the movement of the patient moves the support system **3900** along the support track. Similarly stated, the patient pulls the support system **3900** along the support track. In some instances, a patient may stumble while walking, thereby increasing the amount of force exerted on the support system **3900**. In such instances, the increase in force exerted on the support system **3900** can be sufficient to cause the energy storage member **3960** to move from its first configuration towards its second configuration (e.g., compress). In this manner, the piston **3950** can move relative to the cylinder **3941** and the energy storage member **3960** can absorb at least a portion of the increase in the force exerted on the support structure **3900**. Thus, if the patient stumbles the support system **3900** can dampen the impulse experienced by the patient that would otherwise result in known passive support systems **3900**.

Although the support system **3900** is described as including an energy storage member, in other embodiments, the support system **3900** need not include the energy storage member. For example, in some embodiments, the support system **3900** can be coupled to, for example, the attachment mechanism **2800** described above with reference to FIG. **34**. In this manner, the attachment mechanism **2800** can be used to dampen at least a portion of a change in force exerted on the support system **3900**. For example, in some instances a patient coupled to the support system **3900** may stumble, thereby increasing the force exerted on the support system **3900**. In such instances, the increase in force can move the first arm **2820** towards the second arm **2840** (see e.g., FIG. **34**), thereby moving the energy storage member **2850** towards their second configuration. Thus, at least a portion of the increase in force can be absorbed by the attachment mechanism **2800**.

Although not shown in FIG. **2-36**, one or more active support system (e.g., the support system **2000**) and/or one or more passive support system (e.g., the support system **3900**) can be disposed about a similar support track and can be utilized at the same time. For example, FIG. **37** is a schematic illustration of a support system **4000** according to an embodiment. The support system **4000** includes a support track **4050**, a first support member **4100**, and a second support member **4900**. The support system **4000** can be used to support at least a portion of the body weight of one or more patients during, for example, gait therapy (e.g., after injury), gait training (e.g., low gravity simulation), and/or the like. The support track **4050** is configured to support the weight of the first support member **4100** and the second support member **4900** and the weight of the patient utilizing the first support member **4100** and/or the second support member **4900**.

As shown in FIG. **37**, the support track **4050** can form a closed loop track. The support track **4050** can be similar to or the same as the support track **2050**, described above with reference to FIGS. **2** and **3**; the first support member **4100** can be similar to or the same as the trolley **2100**, described above with reference to FIGS. **2-33**; and the second support member **4900** can be similar to or the same as the support system **3900**, described above with reference to FIGS. **35** and **36**. In this manner, the first support member **4100** and the second support member **4900** can be hung from the support track **4050**, as described in detail above.

In some embodiments, a first patient (not shown in FIG. **37**) can be coupled to the first support member **4100** and a second patient (not shown in FIG. **37**) can be coupled to the second support member **4900** with both being suspended from the support tack **4050**. As shown in FIG. **37**, the first support member **4100** can move in the direction of the arrow A in response to a movement of the first patient coupled thereto. Similarly, the second support member **4900** can be moved in the direction of the arrow B in response to a movement of the second patient coupled thereto. Expanding further, the first support member **4100** can be an active support member and can be configured to move in accordance with the movement of the first patient, as described in detail above. Conversely, the second support member **4900** can be a passive support member and can be moved by the second patient coupled thereto, as described in detail above.

Although the support system **4000** is shown and described as including the first support member **4100** and the second support member **4900**, in other embodiments, the support system **4000** can include any suitable number of support members movably coupled to the support track **4050**. Moreover, any combination of active support members and passive support members can be included in the support system **4000**. For example, while shown as including an active support member (e.g., the first support member **4100**) and a passive support member (e.g., the second support member **4900**), in other embodiments, the support system **4000** can include two active support members, two passive support members, two active support members and two passive support members, or any other suitable combination thereof.

Although not shown in FIG. **37** the support system **4000** (i.e., the first support member **4100** and/or the second support member **4900**) can include a collision management system that is configured to prevent and/or mitigate the impact, force, or effect of a collision between the first

support member **4100** and the second support member **4900**. For example, in some embodiments, the first support member **4100** can include a sensor (e.g., an ultrasonic proximity sensor or the like) configured to sense the position of the first support member **4100** relative to the second support member **4900**. Thus, when the distance between the first support member **4100** and the second support member **4900** approaches a predetermined threshold (e.g., a minimum distance), an electronic system (e.g., similar to or the same as the electronic system **2700** described above) included in the first support member **4100** can send a signal to a drive system (not shown) to increase or decrease a rotational velocity of one or more drive wheels. Thus, a collision of the first support member **4100** and the second support member **4900** can be avoided. In other embodiments, the collision management system can increase or decrease the velocity of one or more drive wheels to substantially reduce a force associated with a collision between the first support member **4100** and the second support member **4900**.

While the first support member **4100** is described above as including a sensor and/or the like that is configured to sense the position of the first support member **4100** relative to the second support member **4900**, in other embodiments, a support system can include any suitable member, device, mechanism, assembly, and/or the like that is configured to substantially maintain a distance between a first support member and a second support member included therein and/or otherwise reduce a force associated with or a likelihood of a collision. In other embodiments, a support system can include and/or can be coupled to any suitable member, device, mechanism, assembly, and/or the like that is configured to prevent direct contact between a first support member and a second support member (e.g., is disposed and/or coupled therebetween). For example, FIGS. **38-40** illustrate a support system **5000** according to an embodiment. The support system **5000** includes a first support member **5100**, a second support member **5100'**, a collision management assembly **5080**, and a support track **5050**. The support track **5050** can be similar to or the same as the support track **2050** (described above with reference to FIGS. **2** and **3**) and/or the support track **4050** (described above with reference to FIG. **37**). The first support member **5100** and the second support member **5100'** can be substantially similar to each other and can each be substantially similar to or the same as the trolley **2100**, described above with reference to FIGS. **2-33**. As such, the first support member **5100** (e.g., a first trolley) and the second support member **5100'** (e.g., a second trolley) can each be active support systems that are hung from the support track **5050**. More specifically, as shown in FIG. **38**, the support track **5050** includes a horizontal portion **5051** and a vertical portion **5052** about which a drive mechanism of the support members **5100** and **5100'** can be disposed, thereby allowing the support members **5100** and **5100'** to move along a length of the support track **5050** in response to a motion of a supported patient, as described in detail above. Thus, the form and function of the support members **5100** and **5100'** are not described in further detail herein.

The collision management assembly **5080** of the support system **5000** can be coupled to and/or otherwise disposed between the first support member **5100** and the second support member **5100'**. In some embodiments, the collision management assembly **5080** can be coupled to the first support member **5100** or the second support member **5100'**. For example, as shown in FIG. **38**, the collision management assembly **5080** includes a coupling portion **5090** that is coupled to the first support member **5100** and a trolley portion **5085** that is movably disposed about the support track **5050**. The trolley portion **5085** can be substantially similar in form and/or function as the first coupling portion **3910** of the support system **3900** described above with reference to FIG. **35**. As such, the trolley portion **5085** includes a set of wheels **5086** that are configured to roll along the horizontal portion **5051** or the vertical portion **5082** of the support track **5050**, as described in detail above.

The trolley portion **5085** also includes a set of bumpers **5087** that extend from a surface of the trolley portion **5085**. In some embodiments, the bumpers **5087** can be formed from a relatively elastic material (e.g., rubber, silicone, polyethylene, polypropylene, polyurethane, and/or the like including copolymers and combinations thereof) that can be configured to absorb at least a portion of a force when placed in contact with an object. More specifically, in some instances, a force can be exerted that can move the trolley portion **5085** along the support track **5085** to place the bumpers **5087** in contact with an object (e.g., the second support member **5100'**). The arrangement of the bumpers **5087** can be such that when the bumpers are placed in contact with the object, at least a portion of the force exerted to move the trolley portion **5085** along the support track **5050** is absorbed by the bumpers **5087**, resulting in a deformation (e.g., an elastic or non-permanent deformation) thereof. In some instances, the deformation of the bumpers **5087** can be such that a portion of the force transmitted through the bumpers **5087** and onto the object (e.g., the second support member **5100'**) is reduced, which can reduce damage to and/or fatigue of a portion of the object. Similarly stated, the bumpers **5087** can be formed from and/or can otherwise include a material that can absorb at least a portion of an impact force between the trolley portion **5085** and an object (e.g., a wall, a support member, and/or the like).

As described above, the coupling portion **5090** is coupled to a portion of the first support member **5100**. More particularly, a first end portion **5092** of the coupling portion **5090** is rotatably coupled to the portion of the first support member **5100**. For example, the first end portion **5092** can include a rotatable eyelet or the like that can be coupled to the portion of the first support member **5100** via, for example, a bolt, pin, post, and/or the like, thereby defining an axis about which the first eyelet can rotate. Similarly, a second end portion **5094** of the coupling portion **5090** can be rotatably coupled to a portion of the trolley portion **5085**. Thus, the coupling portion **5090** can couple or otherwise form a linkage between the first support member **5100** and the trolley portion **5085** such that movement of the first support member **5100** along the support track **5050** moves the trolley portion **5085** along the support track **5050**. For example, the coupling portion **5090** can be configured to transmit, transfer, and/or otherwise exert at least a portion of a force, associated with movement of the first support member **5100** along the support track **5050**, on the trolley portion **5085**. Moreover, the rotatable coupling of the coupling portion **5090** to the first support member **5100** and the trolley portion **5085** can be such that the first support member **5100** can push the trolley portion **5085** along a support track that is substantially nonlinear, as shown in FIG. **38**.

The coupling portion **5090** can be any suitable member, device, and/or mechanism. For example, in some embodiments, the coupling portion **5090** can be a substantially rigid rod or the like that is configured to maintain a substantially fixed distance between the trolley portion **5085** and the first support member **5100**. In other embodiments, the coupling portion **5090** can be substantially non-rigid wherein a dis-

tance between the first support member **5100** and the trolley portion **5085** can be varied (i.e., non-fixed). For example, in some embodiments, a first portion **5091** of the coupling portion **5090** can be configured to move relative to a second portion **5092** of the coupling portion **5090**. Moreover, in some embodiments, the coupling portion **5090** can be configured to absorb at least a portion of a force (associated with movement of the first support member **5100** along the support track **5050**) that would otherwise be exerted on the trolley portion **5085**. For example, as shown in FIGS. **38-40**, the coupling portion **5090** can be a piston-cylinder configuration, wherein a region of the first portion **5091** (e.g., a piston) is movably disposed in the second portion **5093** (e.g., a cylinder). Furthermore, an energy storage member **5095** (e.g., a spring or the like) can be disposed in the second portion **5093** of the coupling portion **5090**, as shown in FIG. **40**. In this manner, movement of the first portion **5091** relative to the second portion **5093** can increase a potential energy of the energy storage member **5095**. For example, in some embodiments, the energy storage member **5095** can be a spring that can be transitioned from a substantially non-compressed configuration (i.e., a relatively lower potential energy) to a substantially compressed configuration (i.e., a relatively higher potential energy) when the first portion **5091** is moved relative to the second portion **5093**. The energy storage member **5095** can be configured to allow the first portion **5091** to move relative to the second portion **5093**, for example, up to about 0.5 inches (0.5"), about 1", about 1.5", about 2", about 2.5", about 3", about 4", about 5", about 7", about 10", or any suitable distance or fraction therebetween. Thus, the coupling portion **5090** can be configured to absorb at least a portion of energy and/or force that would otherwise be transferred and/or transmitted between the first support member **5100** and the trolley portion **5085**. Although the energy storage member **5095** is shown and described as being a spring, in other embodiments, the energy storage member **5095** can be any suitable device, member, and/or volume such as, for example, a volume of a compressible gas and/or the like.

In use, the collision management assembly **5080** can be included in the support system **5000** to substantially prevent a collision between the first support member **5100** and the second support member **5100'** (see e.g., FIG. **38**). Similarly stated, the collision management assembly **5080** can be included in the support system to substantially prevent direct contact between the first support member **5100** and the second support member **5100'**. For example, in some instances, it can be desirable to maintain a distance between the first support member **5100** and the second support member **5100'** that is greater than a predetermined minimum distance and/or a distance threshold. In this manner, the collision management assembly **5080** can be coupled to the first support member **5100** such that when the first support member **5100** and the second support member **5100'** move along the support track **5050** substantially independent from one another, a distance therebetween is maintained that is greater than the predetermined minimum distance and/or distances threshold. For example, in some instances, the first support member **5100** can move relative to the second support member **5100'** such that a distance therebetween is reduced to an extent that places the bumpers **5087** of the trolley portion **5085** in contact with a portion of the second support member **5100'**. Thus, the collision management assembly **5080** can maintain the first support member **5100** and the second support member **5100'** at a distance that is greater than the minimal distance, thereby preventing direct contact (i.e., a direct collision) therebetween. Moreover, the arrangement of the bumpers **5087** and the coupling portion **5090** is such that as the collision management assembly **5080** is brought into contact with the portion of the second support member **5100'** at least a portion of a force associated with the impact is absorbed (e.g., the bumpers **5087** can be transitioned from a non-deformed to a deformed configuration and/or the energy storage member **5095** can be transitioned from a lower potential energy configuration to a higher potential energy configuration). In this manner, an acceleration and/or a jerk (e.g., the rate of change in the acceleration) of the first support member **5100** and/or the second support member **5100'** is not rapidly changed as the collision management assembly **5080** is brought into contact with the second support member **5100'**. In some instances, once the collision management assembly **5080** is placed in contact with the second support member **5100'**, the first support member **5100** and the second support member **5100'** can move along the support track **5050** substantially congruently. In other words, when the collision management assembly **5080** is placed in contact with the second support member **5100'**, the collision management assembly **5080** can push the second support member **5100'** such that the first support member **5100**, the second support member **5100'**, and the collision management assembly **5080** collectively move along the support track **5050** at substantially the same speed.

In some embodiments, the collision management assembly **5080** and/or a portion of the support members **5100** and/or **5100'** can include, for example, one or more sensors or the like that can sense and/or detect one or more parameters associated with the collision management assembly **5080**. For example, in some embodiments, the trolley portion **5085** of the collision management assembly **5080** can include a sensor such as, for example, an accelerometer or the like that can sense and/or otherwise detect and acceleration of the trolley portion **5085** when the bumper **5087** is placed in contact with the second support member **5100'**. In some instances, the sensor can send a signal associated with the acceleration of the trolley portion **5085** to, for example, the electronic system of the first support member **5100**. As such, the electronic system can be configured to control one or more systems (e.g., a drive system or the like) of the first support member **5100** based at least in part on the signal received from the sensor. For example, in some instances, the electronic system can reduce a velocity of the first support member **5100** based at least in part on information received from the sensor of the collision management assembly **5080**.

Although the collision management assembly **5080** is shown and described as being coupled to the first support member **5100** and placed in contact the second support member **5100'** (see e.g., FIG. **38**), in other embodiments, the collision management assembly **5080** can be rotatably coupled to the second support member **5100'** and placed in contact with the first support member **5100** in a similar manner as described above. In addition, while the second support member **5100'** is shown and described as being substantially similar to the first support member **5100** (i.e., an active support member), in other embodiments, the second support member **5100** can be a passive support member such as, for example, the support system **3900** described above with reference to FIGS. **35** and **36**.

While the support system **5000** is described above as including the collision management assembly **5080** to substantially maintain a distance between the first support member **5100** and the second support member **5100**, in other embodiments, a support system can include any suitable

member, device, mechanism, assembly, and/or the like that is configured to absorb at least a portion of energy that is associated with a collision between a support member and another object (e.g., a second support member, a wall, and/or any other obstruction). For example, FIGS. **41-42** illustrate a support system **6000** according to an embodiment. The support system **6000** includes a support member **6900** movably disposed about a support track **6050**. The support track **6050** can be similar to or the same as the support track **2050** (described above with reference to FIGS. **2** and **3**) and/or the support track **4050** (described above with reference to FIG. **37**). The support member **6900** can be substantially similar to the support system **3900**, described above with reference to FIGS. **35-36**. As such, the support member **6900** can be, for example, a passive support system that is hung from the support track **6050**. More specifically, as shown in FIGS. **41** and **42**, the support track **6050** includes a horizontal portion **6051** and a vertical portion **6052** about which a drive mechanism **6910** (e.g., similar to or the same as the first coupling portion **3910** of the support system **3900** described above) of the support member **6900** can be disposed, thereby allowing the support member **6900** to move along a length of the support track **6050** in response to a motion of a supported patient, as described in detail above. Thus, the form and function of the support member **6900** is not described in further detail herein.

As shown in FIGS. **41** and **42**, the support member **6900** can be coupled to and/or can otherwise include a collision plate **6020**. The collision plate **6020** (e.g., a collision management assembly or member) can be any suitable shape, size, or configuration. For example, although the collision plate **6020** is shown as having a substantially circular perimeter, in other embodiments, a collision plate can be any suitable shape such as, square, rectangular, oblong, elliptical, and/or the like. As shown in FIG. **42**, the collision plate **6020** can be coupled to a portion of the support member **6900** such that a surface of the collision plate **6020** in contact with the support member **6900** is substantially parallel to the horizontal portion **6051** of the support track **6050**. Moreover, although not shown in FIGS. **41** and **42**, the arrangement of the support member **6900** can be such that the collision plate **6020** is disposed between the drive portion **6910** and a coupling portion (e.g., such as the second coupling portion **3940** included in the support system **3900** described above with reference to FIG. **36**).

As shown, the collision plate **6020** is configured to extend beyond a perimeter of the support member **6900**. The collision plate **6020** can be formed from and/or can include any suitable material that can be substantially rigid such as, for example, wood, medium density fiber (MDF), plywood, and/or a metal or alloy thereof (e.g., aluminum, aluminum alloy, steel, steel alloy, etc.). In other embodiments, the collision plate **6020** can be formed from and/or can include any suitable material that can be substantially elastic such as, for example, rubber, silicone, polyethylene, polypropylene, polyurethane, nylon, and/or the like including copolymers and/or combinations thereof. The collision plate **6020** includes a bumper **6021** that is coupled to and/or that is otherwise configured to extend from a peripheral surface, as shown in FIGS. **41** and **42**. The bumper **6021** can be any suitable shape, size, and/or configuration. For example, in some embodiments, the bumper **6021** can be formed from and/or can include, for example, expanded foam neoprene, ethylene propylene diene monomer (EPDM) rubber, ethylene-vinyl acetate (EVA) foam, polypropylene (PP) foam, high-density polyethylene (HDPE) foam, low-density polyethylene (LDPE) foam, linear-low-density polyethylene (LLPDE) foam, and/or any other suitable thermoplastic elastomer (TPE) foam, and/or the like. In this manner, the bumper **6021** can be configured to absorb at least a portion of energy that is associated with, for example, an impact. By way of example, in some instances, the support member **6900** can move along the support track **6050** relative to another support member and/or other object until the bumper **6021** of the collision plate **6020** is placed in contact with the other support member and/or other object. More specifically, the support member **6900** can be moved along the support track **6050** with a force resulting from a patient, coupled thereto, dragging or towing the support member **6900** (as described above). In some instances, the support member **6900** can be moved relative to another object on or supported by the support track **6050** in such a manner that the support member **6900** and the other object (e.g., a second support member or the like) collide. Thus, with the collision plate **6020** coupled to the support member **6900** and the bumper **6021** extending beyond the support member **6900**, the bumper **6021** is placed in contact with the other object, resulting in an elastic deformation of the bumper **6021** in response to at least a portion of a force associated with the collision. As such, the bumper **6021** can absorb at least a portion of the energy associated with the collision to, for example, protect and/or otherwise minimize damage to the support member **6900** and/or other object that can otherwise result from the collision.

Although the support track **4050** is shown and described above as being a substantially closed-loop track, in other embodiments, a support track can be an open-loop track. By way of example, in some embodiments, a support track can have a first end portion that is substantially discrete from a second end portion (i.e., an open-loop configuration). In some embodiments, such a support track can include, for example, an end stop or the like that can be configured to substantially limit movement of a support member, support system, trolley, etc., prior to reaching the end of the support track. For example, FIGS. **43** and **44** illustrate a support track **7050** including a track stop **7060**, according to an embodiment. The support track **7050** can be substantially similar to the support track **2050** described above. As such, the support track **7050** can include a horizontal portion **7051** and a vertical portion **7052** and can be configured to support a support system such as, for example, the trolley **2100** and/or the support system **3900**.

The track stop **7060** includes a trolley portion **7065** and a coupling portion **7070**. The trolley portion **7065** can be substantially similar in form and/or function as the trolley portion **5085** included in the collision management assembly **5080** described above with reference to FIGS. **38-40**. As such, the trolley portion **7065** includes a set of wheels **7066** that are configured to roll along the horizontal portion **7051** or the vertical portion **7062** of the support track **7050**, as described in detail above. The trolley portion **7065** also include at least one bumper **7067** that extends from a surface of the trolley portion **7065** (e.g., away from an end surface of the support track **7050**). In some embodiments, the bumper **7067** can be formed from a relatively elastic material (e.g., rubber, silicone, polyethylene, polypropylene, polyurethane, and/or the like including copolymers and combinations thereof) that can be configured to absorb at least a portion of a force when placed in contact with an object, as described in detail above. The arrangement of the bumper **7067** can be such that when placed in contact with, for example, a support member, at least a portion of the force exerted to move the support member along the support track **7050** is absorbed by the bumper **7067**, resulting in a defor-

mation (e.g., an elastic or non-permanent deformation) thereof, which can reduce damage to and/or fatigue of a portion of the support member, as described in detail above.

The coupling portion **7070** is coupled to the end portion of the support track **750** and a portion of the trolley portion **7065**, as shown in FIG. **43**. More particularly, a mounting bracket **7075** is coupled to the end portion of the support track **7050** and is configured to couple and/or otherwise mount the coupling portion **7070** to the support track **7050**. The coupling portion **7070** can be any suitable member, device, and/or mechanism. For example, in some embodiments, the coupling portion **7070** can be a piston-cylinder device, a strut, and/or the like. As such, the coupling portion **7070** includes a first member **7071** (e.g., a piston) that can be moved relative to a second member **7073** (e.g., a cylinder). For example, at least a portion of the first member **7071** can be movably disposed in the second member **7073**. More particularly, an attachment member **7072** of the first member **7071** is rotatably coupled to the trolley portion **7065** (as described above) and in turn, the first member **7071** is configured to move substantially concurrently with the trolley portion **7065**. Similarly stated, the attachment member **7072** rotatably couples the first member **7071** to the trolley portion **7065** such that as the trolley portion **7065** is moved along the support track **7050**, the first member **7071** is moved in an axial direction. The second member **7073** of the coupling portion **7070** is fixedly coupled to the mounting bracket **7075**, which is configured to maintain the second portion **7073** in a substantially fixed position relative to the support track **7050**. Thus, movement of the trolley portion **7065** along the support track **7050** moves the first member **7071** of the coupling portion **7070** relative to the second member **7073**, as described in further detail herein.

As shown in FIG. **44**, an energy storage member **7074** (e.g., a spring or the like) is disposed in the second portion **7093** of the coupling portion **7070** and is configured to engage and/or be in contact with at least a surface of the first member **7071**. In this manner, movement of the first member **7071** relative to the second member **7073** can increase a potential energy of the energy storage member **7074**. For example, in some embodiments, the energy storage member **7074** can be a spring (as shown in FIG. **44**) that can be transitioned from a substantially non-compressed configuration (i.e., a relatively lower potential energy) to a substantially compressed configuration (i.e., a relatively higher potential energy) when the first member **7071** is moved relative to the second member **7073**. The energy storage member **7074** can be configured to allow the first member **7071** to move relative to the second member **7073**, for example, up to about 0.5 inches (0.5"), about 1", about 1.5", about 2", about 2.5", about 3", about 4", about 5", about 7", about 10", or any suitable distance or fraction therebetween. Thus, the coupling portion **7070** can be configured to absorb at least a portion of energy and/or force, as described in further detail herein. Although the energy storage member **7074** is shown and described as being a spring, in other embodiments, the energy storage member **7074** can be any suitable device, member, and/or volume such as, for example, a volume of a compressible gas and/or the like.

In use, the track stop **7060** can be included in the support system **7000** to substantially prevent a support member and/or trolley (not shown in FIGS. **43** and **44**) from reaching an end of a support track **7050** when moving along a length thereof. For example, a support member can move along the support track **7050** and towards the end portion to a position in which a portion of the support member is placed in contact with the bumper **7067** of the trolley portion **7065**. Thus, the support member exerts a force on the bumper **7067** that can transition the bumper **7067** from a non-deformed configuration to a deformed configuration, thereby absorbing at least a portion of the force and/or kinetic energy. Moreover, the force exerted by the support member can move the trolley portion **7065** along the support track **7050**, which in turn, moves the first member **7071** of the coupling portion **7070** relative to the second member **7073** of the coupling portion **7070**. Accordingly, with the first member **7071** in contact with the energy storage member **7074**, the movement of the first member **7071** relative to the second portion **7072** can transition the energy storage member **7074** from a lower potential energy configuration to a higher potential energy configuration. In this manner, an acceleration and/or a jerk (e.g., the rate of change in the acceleration) of the support member is not rapidly changed as the track stop **7060** limits further movement of the support member along the support track **7050**. Furthermore, by absorbing at least a portion of the kinetic energy and/or force exerted by the support member, damage to the support member that can otherwise result from the support member hitting a "hard stop" (e.g., a stop mechanism with little or no energy absorption).

Although the trolley **2100** is described above as including the encoder **2470** of the drive system **2300**, the encoder **2561** of the guide mechanism **2540**, and the encoder **2587** of the cam assembly **2570**, which are collectively used to determine one or more system parameters (e.g., position, velocity, acceleration, etc.), in other embodiments, a trolley and/or the like can include any suitable device, mechanism, and/or system configured to determine one or more system parameters. For example, FIGS. **45-47** are schematic illustrations of a trolley **8100** including an optical tracking system **8720**, according to an embodiment. The trolley **8100** (e.g., a support member) can be substantially similar to or the same as the trolley **2100**, described above with reference to FIGS. **2-33**. As such, the trolley **8100** is an active support system that is hung from a support track (not shown in FIGS. **45-47**). The trolley **8100** can differ from the trolley **2100**, however, with the inclusion of the optical tracking system **8720**, as described in further detail herein.

The optical tracking system **8720** includes at least an imaging device **8725** and a tracking member **8860**. As shown in FIG. **45**, the tracking member **8860** can be coupled to and/or included in a patient attachment mechanism **8800**, which can otherwise be substantially similar to the patient attachment mechanism **2800** described above with reference to FIG. **34**. The patient attachment mechanism **8800** is operably coupled to the trolley **8100** by a tether **8505**. The tether **8505** can be substantially similar to or the same as the tether **2505** included in the support system **2500** described above with reference to FIGS. **27-33**. The tracking member **8860** can be any suitable shape, size, and/or configuration. For example, in some embodiments, the tracking member **8860** can be a substantially spherical or oblong ball. Although not shown in FIGS. **45-47**, the tracking member **8860** can include a surface finish that can facilitate an optical tracking. For example, in some embodiments, the tracking member **8860** can include a surface having a color and/or pattern that can be used to identify, for example, position information such as relative linear position, relative angular position, absolute position, etc. Moreover, information associated with the color, the pattern, the size, the shape, and/or the like of the tracking member **8860** can be stored, for example, in a memory included in an electronic system (e.g., substantially similar to the electronic system **2700** of the trolley **2100** (not shown in FIGS. **45-47**)) of the trolley **8100**.

The imaging device **8725** of the optical tracking system **8720** can be any suitable imaging device. For example, in some embodiments, the imaging device **8725** can be a camera and/or the like that can capture discrete pictures and/or can continuously record a video stream. The imaging device **8725** is coupled to the trolley **8100** and is maintained in a fixed position relative thereto. Although not shown in FIGS. **45-47**, the imaging device **8725** is operably coupled to the electronic system of the trolley **8100**. Thus, the imaging device **8725** can be configured to send a signal representing data associated with captured images and/or video streams and, upon receipt, the electronic system can store the data in, for example, the memory and/or the like. Furthermore, the memory of the electronic system can store data associated with the position of the imaging device **8725** or a portion of the imaging device **8725** (e.g., a lens, aperture, focal point, charge-coupled device (CCD) sensor, a complementary metal-oxide-semiconductor (CMOS) sensor, and/or the like), relative to a portion of the trolley **8100**. As such, the electronic system of the trolley **8100**, and more specifically, a processor and/or module can determine, for example, a reference coordinate system relative to the imaging device **8725** and/or a portion of the trolley **8100**.

In some instances, the imaging device **8725** can be used to capture one or more images and/or video streams of the tracking member **8860** while in use during, for example, gait training and/or the like. For example, as shown in FIGS. **46** and **47**, the optical tracking system **8720** can be used to determine a first position P and a second position P' of the tracking member **8860** and thus, the patient attachment mechanism **8800**. More specifically, in some instances, a patient (not shown) can be coupled to the patient attachment mechanism **8800** (e.g., via a harness or the like, as described above) and can perform a gait training therapy session, thereby moving the patient attachment mechanism **8800** relative to the trolley **8100** and the trolley along the support track (not shown in FIGS. **45-47**). During use, the imaging device **8725** can capture one or more images and/or video streams of the tracking member **8860** to determine, for example, the first position P and the second position P' of the tracking member **8860**. More specifically, as shown in FIG. **46**, the imaging device **8725** can capture one or more images and/or video streams and can send a signal representing data associated with the one or more images and/or video streams to the processor and/or to a module (e.g., a processing module) included in the electronic system. The processor and/or module can, for example, analyze the image and can calculate a distance D of the image of the tracking member **8860** from a reference plane R and a size S of the image of the tracking member **8860**. Based at least in part on the calculated distance D and the calculated size S, the processor and/or module can determine and/or calculate an angle A of the tether **8505**, a length L of the tether **8505**, and a distance H of the tracking member **8860** from the trolley **8100** (FIG. **47**), thereby determining the first position P of the tracking member **8860** and the patient attachment mechanism **8800**. Similarly, when the patient moves from the first position P, the imaging device **8725** can capture one or more images and/or video streams and can send a signal representing data associated with the new images and/or video streams to the processor and/or module. As such the processor and/or module can, for example, analyze the image and can calculate a second distance D' of the image of the tracking member **8860'** from the reference plane R and a second size S' of the image of the tracking member **8860'**. Based at least in part on the calculated second distance D' and the calculated second size S', the processor and/or module can determine and/or calculate a second angle A' of the tether **8505'**, a second length L' of the tether' **8505**, and a second distance H' of the tracking member **8860'** from the trolley **8100** (FIG. **47**), thereby determining the second position P' of the tracking member **8860'** and the patient attachment mechanism **8800'**.

Although the trolley **2100** is described above as including the encoder **2470** of the drive system **2300**, the encoder **2561** of the guide mechanism **2540**, and the encoder **2587** of the cam assembly **2570**, which are collectively used to determine one or more system parameters (e.g., position, velocity, acceleration, etc.), and the trolley **8100** is described above as including the optical tracking system **8720** to determine the one or more system parameters, in other embodiments, a trolley and/or support system can use any suitable combination of an encoder system and an optical tracking system. For example, in some embodiments, a trolley can use data from any number of encoders (e.g., of a drive system, guide mechanism, and/or cam assembly) and an optical tracking system.

While the trolleys **2100** and **8100** are described above as including an electronic system (e.g., the electronic system **2700**) that actively controls the operating condition of the trolleys **2100** and **8100** to support at least a portion of the weight of the patient, in some embodiments, a trolley can include an electronic system, which, in addition to controlling the operating condition of the trolley, can determine one or more characteristics associated with the patient's gait during use. By way of example, a trolley such as the trolley **2100** and/or **8100** can include a set of encoders, sensors, and/or the like that can determine a set of operating conditions associated with a portion of the trolley. Specifically, in some embodiments, the trolley can include a drive system similar to the drive system **2300** in FIGS. **12-26**, a patient support mechanism similar to the patient support mechanism **2500** in FIGS. **27-33**, and an electronic system similar to the electronic system **2700** in FIGS. **10** and **11**, which can be used collectively to determine the set of operating conditions associated with the trolley. In turn, the electronic system can determine, based on the set of operating conditions, the one or more characteristics associated with the patient's gait during use.

By way of example, in some embodiments, the patient support mechanism can include, inter alia, a winch assembly coupled to a tether, a guide mechanism, and a cam assembly. The winch assembly can have an encoder (e.g., similar to the encoder **2537**), the guide mechanism can have an encoder (e.g., similar to the encoder **2561**), and the cam assembly can have an encoder (e.g., similar to the encoder **2587**). Similarly, the drive system can have an encoder (e.g., similar to the encoder **2470**). The electronic system can include at least a processor and a memory configured to receive one or more signals from the encoders of the drive mechanism and the patient support mechanism. In some embodiments, the electronic system can also include an imaging device (e.g., similar to the imaging device **8725** in FIGS. **46** and **47**) configured to capture and image or video stream of a tracking member (e.g., similar to the tracking member **8860**).

As described in detail above, when a patient using the patient support system begins to walk, the drive mechanism can move the trolley along the support track in response to his or her movement. The encoder of the drive mechanism can, in turn, sense one or more characteristics associated with the operation of the drive mechanism. For example, the encoder can sense a position of the drive mechanism relative to the support track, a translational velocity of the drive

mechanism along the support track, a translational acceleration of the drive mechanism along the support track, a rotational velocity of one or more wheels, a rotational acceleration of one or more wheels, an angular orientation of one or more wheels, a motor speed and/or direction, a voltage associated with at least a portion of the motor, and/or the like. The encoder can then send a signal associated with the one or more characteristics of the drive mechanism to the electronic system, which in response, can cause the processor to determine and/or or update an operating condition of the drive mechanism based at least in part on a change in the one or more characteristics of the drive mechanism relative to a previously defined operating condition of the drive mechanism (e.g., stored in a memory or the like), as described in detail above with reference to the trolley **2100**.

Similarly, in response to the walking of the patient, the encoder of the winch assembly, the guide mechanism, and/or the cam assembly (as well as the imaging device if included therein) can sense and/or determine one or more characteristics associated with the operation of the patient support mechanism. For example, in some instances, the patient may walk faster than the trolley, thereby changing the angle of the tether and the guide mechanism relative to the trolley. The encoder of the guide mechanism can sense the angular deflection of the guide mechanism and can send a signal associated with the angle of the guide mechanism to the electronic system. Upon receipt, the electronic system can cause the processor to determine and/or update an operating condition of the guide mechanism.

In some instances, the movement of the patient may, for example, increase a length of a portion of the tether. As such, a portion of the tether can be unspooled from a drum or the like included in the winch assembly. More specifically, at least a portion of a force exerted by the patient on the tether can rotate the drum or the like, which in turn, results in an unspooling of the tether (i.e., an increase in a length of a portion of the tether between the patient and the winch assembly). The encoder of the winch assembly can sense one or more characteristics associated with the operation of the winch assembly. For example, the encoder can sense an angular position of the drum, a rotational velocity of the drum, an acceleration of the drum, a speed and/or direction of a motor included in the winch assembly, a voltage associated with at least a portion of the motor of the winch assembly, and/or the like. The encoder can then send a signal associated with the one or more characteristics of the winch assembly to the electronic system, which in response, can cause the processor to determine and/or or update an operating condition of the winch assembly based at least in part on a change in the one or more characteristics of the winch assembly relative to a previously defined operating condition of the winch assembly (e.g., stored in a memory or the like), as described in detail above with reference to the trolley **2100**. In some instances, based at least in part on the updated operating condition of the winch assembly, the processor can determine a length of the portion of the tether disposed between the patient and the winch assembly. In some embodiments, the tether can be coupled to a load cell or the like configured to sense a force exerted by the patient on the tether (e.g., by measuring a stress, tension, strain, and/or the like along and/or within a portion of the tether). The load cell can be configured to send a signal to the electronic system associated with a load (e.g., force) exerted on the tether, which in turn, can cause the processor to determine a force exerted by the patient.

In some instances, an amount of force exerted on the tether by the patient may increase or decrease in a substantially sudden manner. For example, if a patient stumbles, an amount of force exerted on the tether may increase relatively suddenly. In such instances, the increase of force exerted on the tether may pivot the guide mechanism and/or increase a length of a portion of the tether (as described above), as well as rotate a cam and/or cam arm included in the cam assembly (e.g., as described with reference to the cam assembly **2570** in FIGS. **32** and **33**). In other words, at least a portion of the cam assembly can be configured to rotate in response to a relatively fast movement and/or deflection of the tether. The encoder of the cam assembly can sense one or more characteristics associated with a movement of the cam and/or cam arm such as, for example, position, velocity, acceleration, jerk, orientation, alignment, force, and/or the like. The encoder of the cam assembly can then send a signal associated with the one or more characteristics of the cam assembly to the electronic system, which in response, can cause the processor to determine and/or update an operating condition of the cam assembly based at least in part on a change in the one or more characteristics of the cam assembly relative to a previously defined operating condition of the cam assembly (e.g., stored in memory), as described above with reference to the trolley **2100**.

By defining, determining, and/or updating one or more operating conditions of the drive mechanism and/or the patient support mechanism, the electronic system (e.g., at least the processor of the electronic system) can actively control the trolley to support at least a portion of a weight of the patient using the patient support system. As described above, in some instances, the magnitude of change in the operating condition of the drive system and/or the patient support mechanism is based at least in part on a proportional-integral-derivative (PID) control. In such instances, the electronic system (e.g., the processor or any other electronic device in communication with the processor) can determine the changes of the patient support mechanism and model the changes based on the PID control. Based on the result of the modeling the processor can determine the suitable magnitude of change in the operating condition of the drive system and/or the patient support mechanism.

For example, FIG. **48** is a schematic illustration of a control diagram according to an embodiment. In this embodiment, the electronic system (described above) can be configured to control the drive system and/or the patient support mechanism based at least in part on a tension within and/or along a portion of the tether. Specifically, a nurse, technician, therapist, doctor, physician, etc. can define a predetermined value associated with a target tether tension T* (e.g., commanded tether tension). With the commanded tether tension T* stored, for example, in memory, the processor of the electronic system can compare an actual tension T within and/or along the portion of the tether against the commanded tether tension T* to determine a tension error. In some instances, the processor can then perform a derivative control operation **101** on the tension error, the output of which can be added to one or more proportional control operation outputs (described in further detail below) to determine, for example, a motor speed command ω_M* for controlling motor and drive dynamics **102** associated with a motor included in the drive system and/or the patient support mechanism.

As shown in FIG. **48**, a proportional control operation **103** can be performed on a value associated with an actual motor speed ω_M of the motor included in the drive system and/or patient support mechanism. In addition, the actual motor speed ω_M can be evaluated with a value Z associated with a downward motion of the tether (e.g., in response to a force

exerted by a patient) for controlling spring mechanism dynamics **104** associated with, for example, the cam assembly of the patient support mechanism. As a result, the processor can define (1) an updated value of the actual tension T within and/or along the portion of the tether, and (2) a cam unloading rotation speed ω_C. An equivalent motor speed can be determined by evaluating a rotational speed associated with a portion of the cam and a rotational speed associated with, for example, the drum of the winch assembly (represented in FIG. **48** by the reference numeral **105**). A proportional control operation **106** can be performed on the equivalent motor speed, an output of which can then be added to an output of the proportional control operation **103**. As described above, the sum of the proportional control operations **103** and **106** can be added to the output of the derivative control operation **101** to define the motor speed command ω_M*. Thus, in this embodiment and as described above, the electronic system (e.g., or at least the processor included therein) can control the trolley, in response to movement of a patient, based at least in part on a PID control feedback loop and/or the like.

In some instances, the electronic system can determine one or more characteristic associated with a patient's gait based at least in part on an operating condition and/or a change in operating condition of the drive mechanism and/or the patient support mechanism. For example, FIG. **49** is a graph **200** illustrating a displacement of a center of mass of a patient according to an embodiment. As shown, a patient's center of mass shifts during a gait cycle (e.g., up to about 5 centimeters (cm)), which in turn, results in a shifting and/or changing force exerted on the tether when the patient is using the patient support system. For example, the center of mass of the patient can be at a lowest point (i.e., closest to a surface on which the patient is walking) at about 5% and about 55% of the gait cycle, which corresponds to a termination of a swing phase of the gait cycle. The center of mass of the patient can be at a highest point (i.e., furthest away from the surface on which the patient is walking) at about 30% and about 80% of the gait cycle, which corresponds to the patient's center of mass passing over his or her weight bearing leg. Similarly, the center of mass of the patient can shift in a lateral direction during the gait cycle, as shown in FIG. **49**. With at least a portion of the weight of the patient supported by the patient support mechanism, the shifting of the center of mass of the patient results in a corresponding shift and/or change in the force exerted on the tether by the weight of the patient. Therefore, based on one or more operating conditions associated with the drive system and/or the patient support mechanism, the processor can determine a set of characteristics associated with the patient's gait.

By way of example, FIGS. **50-53** are graphs illustrating operating conditions associated with the patient support mechanism in response to a patient's movement. In this instance, the operating conditions associated with the patient support mechanism relate to a tether position and a cam angle of the cam included in the cam assembly, which in turn, can be used to determine one or more characteristics associated with the patient's gait. More specifically, the processor of the electronic system can determine the tether position based on a signal received from one or more encoders (e.g., the encoder of the winch assembly, the guide member, and/or any other suitable encoder) and can determine the cam angle based on, for example, the encoder of the cam assembly.

As shown in FIG. **50**, the tether position and cam angle are graphed in response to a relatively slow movement of a normal or healthy patient's gait. Specifically, graph **301** illustrates a position of a portion of the tether, with and without factoring in a position associated with the cam, in response to the patient's gait; graph **302** illustrates a cam angle of the cam in response to the patient's gait; graph **303** illustrates a change in the tether position plus a change in the cam angle in response to the patient's gait; and graph **304** illustrates the speed and acceleration associated with the tether in response to the patient's gait. In some instances, the position of the portion of the tether, as shown in graph **301**, can change in response to a relatively slow, gradual, and/or substantial change in the patient's movement, while the cam angle of the cam, as shown in graph **302**, can change in response to a relatively fast, sudden, and/or abrupt movement of the tether. In some instances, the change in cam angle in response to the relatively fast movement of the tether can, for example, reduce noise or the like that might otherwise alter a determination of the tether position. As shown in graph **303**, the change in the tether position and the change in the cam angle can be determined, which in turn, can be used to determine a speed and acceleration associated with the tether position, as shown in graph **304**. Moreover, by determining the tether position, velocity, and acceleration, the processor of the electronic system can determine one or more characteristics associated with the patient's gait. For example, in some instances, the gait of a healthy patient may have and/or define a substantially symmetric characteristic when comparing movement of the patient's left leg to movement of the patient's right leg. Thus, by determining the position, velocity, and acceleration of the tether, the processor can determine gait characteristics such as, for example, a number of steps, a distance traveled, a stride length, a velocity, a difference between gait characteristics associated with the left leg and the right leg, and/or any other suitable characteristic.

In a similar manner, FIG. **51** illustrates graphs showing the tether position and cam angle in response to a relatively fast movement of the normal or healthy patient's gait. Specifically, graph **401** illustrates a position of a portion of the tether, with and without factoring in a position associated with the cam, in response to the patient's gait; graph **402** illustrates a cam angle of the cam in response to the patient's gait; graph **403** illustrates a change in the tether position plus a change in the cam angle in response to the patient's gait; and graph **404** illustrates the speed and acceleration associated with the tether in response to the patient's gait. As can be seen in FIGS. **50** and **51**, the speed associated with the patient's movement can result in a different response of the tether position and the cam angle. Thus, the processor of the electronic system can determine any suitable gait characteristic associated with the patient's relatively fast gait, which can be different from a corresponding gait characteristics associated with the patient's relatively slow gait.

While the graphs in FIGS. **50** and **51** illustrate the tether position and the cam angle relative to a normal or healthy patient's gait, FIGS. **52** and **53** illustrate a tether position and cam angle relative to an impaired patient's gait and more specifically, to the gait of a patient with an impairment resulting in a dragging of one of his or her legs. For example, in FIG. **52**, graph **501** illustrates a position of a portion of the tether, with and without factoring in a position associated with the cam relative to the impaired patient's gait; graph **502** illustrates a cam angle of the cam relative to the impaired patient's gait; graph **503** illustrates a change in the tether position plus a change in the cam angle relative to the impaired patient's gait; and graph **404** illustrates the speed and acceleration associated with the tether relative to the impaired patient's gait. Similarly, in FIG. **53**, graph **601**

illustrates a position of a portion of the tether, with and without factoring in a position associated with the cam relative to circumduction movement of the impaired patient's gait; graph **602** illustrates a cam angle of the cam relative to circumduction movement of the impaired patient's gait; graph **603** illustrates a change in the tether position plus a change in the cam angle relative to circumduction movement of the impaired patient's gait; and graph **604** illustrates the speed and acceleration associated with the tether relative to circumduction movement of the impaired patient's gait.

As can be seen in FIGS. **52** and **53**, the impairment causing the patient to drag one leg during his or her gait results in a response of the tether position and the cam angle that is more erratic, abrupt, and/or otherwise more irregular relative to the response of the tether position and the cam angle resulting from a non-impaired patient's gait. In some instances, the position, velocity, and/or acceleration of the tether position resulting from the impaired patient's gait can be compared to the position, velocity, and/or acceleration of the tether position resulting from the non-impaired patient's gait. As such, the processor of the electronic system can determine, predict, and/or otherwise analyze the characteristics of the impaired patient's gait, which in turn, can be used to define a therapeutic treatment plan, a therapeutic progress report, a diagnostic method, and/or the like.

In some instances, the patient support system (and/or any of the patient support systems described herein) can be used in conjunction with any other suitable device configured to determine, provide, and/or define characteristics associated with a patient's gait. In some instances, the analysis of the one or more operating conditions of the drive mechanism and/or patient support mechanism can be used in conjunction with an analysis of data associated with an electric stimulator configured, for example, to improve an impaired patient's gait. For example, the patient support system can be used to support a patient donning an electric stimulator, configured to facilitate the gait of a patient experiencing drop foot or the like, such as those described in U.S. Patent Publication No. 2014/0303705 entitled, "Orthosis for a Gait Modulation System," filed Apr. 4, 2014, the disclosure of which is incorporated herein by reference in its entirety. As shown in FIG. **54**, the electric stimulator can define one or more operating conditions associated with the electric stimulator and/or the impaired patient's gait. For example, the electric stimulator can sense and/or determine an anterior or posterior motion, a lateral motion, a total motion (e.g., a combination of the lateral motion and the anterior or posterior motion), and/or a pressure associated with a heel on or heel off event, as shown in FIG. **54**. In this instance, graph **701** illustrates an acceleration associated with the operation of the electric stimulator; graph **702** illustrates a speed associated with the operation of the electric stimulator; graph **703** illustrates a rotation associated with the operation of the electric stimulator; and graph **704** illustrates an angle associated with the operation of the electric stimulator.

In some embodiments, the electric stimulator can send a signal associated with one or more of its operating conditions to the electronic system of the patient support system. As such, the processor can determine one or more gait characteristics of the impaired patient based on data received from the drive system and/or patient support mechanism as well as the electric stimulator. By way of example, FIG. **55** illustrates graphical representations of a set of gait characteristics of a patient, which were determined based at least in part on data associated with the patient support system and the electric stimulator (as described in detail above). Specifically, graph **801** illustrates a swing and stance duration of the patient's gait; graph **802** illustrates a swing to stance ratio of the patient's gait; graph **803** illustrates a cadence of the patient's gait; graph **804** illustrates an anterior and lateral range of motion (ROM) associated with one or both of the patient's legs; graph **805** illustrates an anterior to lateral ratio associated with one or both of the patient's legs; and graph **806** illustrates a stride length and height of the patient's gait. Thus, the operating conditions associated with the patient support system and any other suitable device can be used to determine one or more characteristics of the patient's gait. Moreover, the electronic system can be configured to send a signal to any suitable output device (e.g., a monitor, a laptop, a personal computer, a hand held controller, a smartphone, and/or the like) that is indicative of an instruction to output data associated with the one or more characteristics of the patient's gait.

As described above, any of the patient support systems and/or body weight support systems described herein can be used to and/or can otherwise facilitate an analysis of a patient's gait while using that system. For example, in some embodiments, the patient support systems can be used with an electronic device (e.g., a personal computer, laptop, tablet, smartphone, controller, remote display, workstation, server, and/or the like) to determine data associated with the patient's gait and graphically and/or alpha-numerically represent that data on a display. The patient support system can include, for example, a trolley tracking and dynamic body weight engine, module, processor, compute device, etc. to determine data such as trolley speed, travelled distance, tether length, cam angle, body weight unloading, elapsed time, and/or any other suitable data set.

In addition, when a patient support system such as those described herein is used with, for example, an electric stimulator system or with any other suitable electric and/or electronic data collection system, the patient support system can be configured to receive signals from and/or send signals to such electric or electronic systems associated with, for example, heel on or off events and/or other gait phases. Thus, in some instances, the patient support systems described herein can calculate and/or determine a step duration, a step length, a walking speed, a symmetry level of gait patterns (left/right), and/or any other suitable gait characteristic. Moreover, the patient support systems described herein can send one or more signals (e.g., via a wired or wireless connection) to, for example, the electronic device to cause a graphical representation, a numeric representation, and/or an alpha-numeric representation of the calculated and/or determined gait characteristics to be presented on a display. In other instances, the patient support system can send data associated with one or more operating conditions of the patient support system to the electronic device. In such instances, the electronic device can calculate and/or define the gait characteristics, based at least in part on the data received from the patient support system. In addition, the electric stimulator can send data associated with the patient's gait, substantially concurrently with the patient support system, to the electric device. In other instances, the electric stimulator can send data associated with the patient's gait to the patient support system and the patient support system (e.g., a processor, module, or compute device included therein) can aggregate the data associated with the patient support system and the data associated with the electric stimulator and, in turn, can send an aggregated data set to the electronic device.

In some embodiments, the patient support system and/or an electronic device in communication therewith can include

memory and/or at least one module that stores data associated with one or more predetermined exercises, routines, tests, and/or the like. For example, the memory and/or module can include data associated with a set of exercises to analyze the patient's current and/or previous gait tests or analysis to track and help improve the patient's ability to walk. In some instances, the patient support system and/or the electronic device in communication therewith can graphically represent data associated with the exercises, routines, tests, and/or the like.

For example, FIG. **56** is a screenshot **901** illustrating a graphical representation of data associated with an asymmetry exercise. The screenshot **901** of the asymmetry exercise visually shows a patient's vertical asymmetry (leaning more on one side than on the other side) and his or her horizontal asymmetry (difference between step durations). As shown, the symmetry can be displayed in position symmetry bar graphs as well as radio dials, which can be complemented by real time graphs showing a history of, for example, changing tether positions and walking speeds. During and after the asymmetry test, the patient support system and/or the electronic device can send a signal or instruction such that data associated with an average, minimum, and/or maximum walking speed, a vertical and/or horizontal symmetry, and/or the like is graphically represented on the display.

By way of another example, FIG. **57** is a screenshot **902** illustrating a graphical representation of data associated with a timed-up-and-go (TUG) exercise. The screenshot **902** of the TUG exercise can graphically represent data defined by the patient support system and/or the electronic device associated with the time it takes a patient to stand up from a seated position, walk a predetermined distance, and then sit down. During and after the TUG exercise, the patient support system and/or the electronic device can send a signal or instruction such that data associated with an average, minimum, and/or maximum speed during the TUG training exercises is graphically represented on the display. In addition, the patient support system and/or the electronic device can cause data to be graphically represented on the display such as real time graphs showing the history of the stand-up, walking, and sit down process, tether positions (included in a patient support mechanism of the patient support system, as described in detail above), and/or time durations, as well as the walking speeds during the exercise. Based at least in part on the time duration results, a fall risk (e.g., high or low) can be determined for the patient. Moreover, the data associated with the TUG exercise can be compared to historical data (e.g., stored in memory) from that patient's previous TUG exercises, thereby allowing a clinician or therapist to keep track of improvements in patient's gait.

As another example, FIG. **58** is a screenshot **903** illustrating a graphical representation of data associated with a timed-distance exercise. For example, a user (e.g., clinician and/or patient) can select either a fixed distance (e.g., 10 meters) or a fixed time (e.g., 2 minutes). The patient then walks for that distance or that time and the patient support system and/or the electronic device can determine and/or define the patient's performance. For a fixed distance, the timed-distance exercise can determine a gait speed and duration. For a fixed time, the timed-distance exercise can determine a total travelled distance and/or a gait speed. The patient support system and/or the electronic device can cause data to be graphically represented on the display such as real time graphs showing the distance travelled and the walking speed, an average, minimum, and/or maximum walking speed, and/or the like.

As described above, any data associated with the exercises, routines, tests, etc. can be saved, for example, in memory, and can be replayed and/or otherwise presented for post exercise analysis. In addition, data associated with any given exercise can be saved as a baseline so it can be used to compare against future exercises to show the improvements in patient's gait. In some instances, a report can be defined (e.g., by the patient support system and/or the electronic device) and graphically represented on the display to provide details of a given exercise, including the gait speed, distance, time, time to stand, time to sit, cadence, symmetry indexes, or the like, as well as a Perry Ambulatory Category, a Functional Ambulation Category, and/or fall risk.

The patient support mechanism and/or the electronic device (or a processor, module, compute device, etc. included therein) can be configured to perform the exercises, routines, test, or the like, based on data associated with, for example, a tether position, a cam angle, a walking speed, a motor speed, a heel on or off event (and/or other gait phases), and/or the like. In some instances, the patient support mechanism and/or the electronic device can determine, for example, a change in the position of the tether (i.e., included in a patient support mechanism, as described in detail above) between two heel events to determine a vertical symmetry of the patient's gait. In some instances, the data can be based on both linear tether positions and/or cam angles (e.g., a linear graph) and a derivative thereof (e.g., slope or rate of change) of the tether position and/or cam angles (converted to linear length) to determine a gait pattern and/or characteristic.

Based on a determined gait pattern, the patient support mechanism and/or the electronic device can determine peaks and/or valleys associated with the gait events, which can be graphically represented as a linear graph or a derivative graph. In some instances, the patient support mechanism and/or the electronic device can use, for example, a midpoint logic to normalize the linear graph and/or derivative graph (e.g., remove a graph offset, or the like). In some instances, the peaks and valleys of the graphs (e.g., local minima and/or local maxima of the data) can be used determine the heel on or off events. Based on different predetermined gait patterns (e.g., a first category for normal walkers and a second category for pathological walkers) the peaks and valleys can be defined and/or determined differently. For example, for a normal walker, a valley (e.g., locally the shortest tether position) can be about mid stance (double support) of the gait. Conversely, for a pathological walker, a valley can be during a step.

Once the peaks and valleys are associated with the respective heel on or off events, the difference between the previous and current step tether positions can be determined to define the changes in the tether positions (e.g., determine vertical symmetry difference between the right and the left steps or the difference between the two subsequent steps). The previous and current step elapsed times can also be determined to define changes in the step duration (e.g., determine horizontal symmetry).

While the patient support system is described above as using one or more operating conditions to determine gait patterns and/or gait characteristics, in other instances, one or more operating conditions of the patient support system can be used to determine a current level or current amount of body weight support relative to a predetermined level or predetermined amount of body weight support. In some embodiments, a patient support system ("support system") can be programmed and/or set to provide a predetermined

amount of body weight support (or to provide body weight support in a predetermined and/or preprogrammed manner) based on characteristics associated with the tether. For example, in some embodiments, the support system can be configured and/or programmed to provide support to a patient after, for example, a predetermined and/or predefined lengthening of the tether (e.g., in response to a patient falling or partially falling). In other words, the support system can be configured and/or programmed to support at least a portion of the patient's body weight after the patient has fallen beyond a predetermined threshold.

For example, FIGS. **59** and **60** are screenshots **904** and **904**A, respectively, illustrating a graphical representation of data associated with a support system and more particularly, with a "fall prevention" configuration, setting, interface, and/or the like. As described above, in some instances, a support system can be configured to provide support of at least a portion of a patient's body weight based on a lengthening of the tether in response to the patient falling or beginning to fall. In some embodiments, for example the support system and/or an electronics assembly included therein can be configured to determine, define, and/or calculate an initial length of the tether (e.g., when the patient and/or user is stationary and/or not falling). As the patient and/or user begins to walk, the electronics assembly can receive data from one or more sensors, encoders, and/or the like that is associated with a current tether length. In some instances, the patient, user, therapist, and/or trainer can set a fall limit (e.g., a criterion or threshold) that corresponds to a threshold amount a length of the tether can be increased prior to the support system providing support for the patient. In other words, a user, therapist, trainer, etc. can set a fall tolerance and/or maximum distance that a user can fall prior to the support system providing support.

As shown in FIGS. **59** and **60**, in some embodiments, the default fall limit and/or the default threshold amount of lengthening of the tether can be, for example, about 4 inches (in.). After a length of the tether has been increased beyond the threshold (e.g., after a patient and/or user has descended (fallen) beyond the fall limit), the support system can transition to a support configuration in which the tether can be locked and/or a tracking system or drive system is deactivated (e.g., a support configuration or fall prevention configuration). In some instances, the patient, user, and/or clinician can adjust the fall limit and/or threshold by engaging the graphical interface shown, for example, in the screenshot **904**A of FIG. **60** (e.g., by pressing one or more on-screen buttons and/or otherwise by selecting a predetermined fall limit, threshold, and/or criterion). As shown, the adjusted value, limit, and/or threshold can be presented on the graphical interface (e.g., in text or via one or more images).

In some embodiments, for example, the fall limit and/or threshold can be between about 1.0 in. and about 36.0 in. In such embodiments, setting the fall limit to 1.0 in. can be such that the support system provides the highest level of support (e.g., allows the least amount of falling prior to initiating support of the patient), and setting the fall limit to 36.0 in. can be such that the support system provides the lowest level of support (e.g., allows the most amount of falling prior to initiating support of the patient). In some embodiments, the fall limit and/or threshold can be adjusted by increments of about 1.0 in. In other embodiments, the adjustment increments can be greater than 1.0 in. or less than 1.0 in. In some instances, the fall limit and/or threshold can be adjusted and/or changed while the support system is in use or between uses. Moreover, in some instances, the support system and/or electronics assembly can be configured to calculate and/or determine a height of, for example, a patient attachment mechanism and data associated with the height can be graphically represented on a display. For example, as shown in FIGS. **59** and **60**, a height of the tether, patient, and/or patient attachment mechanism can be graphically represented on a bar graph or the like relative to the fall limit and/or threshold, which can allow for substantially real time visualization of a user's performance or the like.

In some embodiments, an administrator or user can program and/or set an initial tether length or the like corresponding to a predetermined and/or desired height of a patient attachment mechanism (e.g., the patient attachment mechanism **2800** described above with reference to FIG. **34**). More specifically, the user and/or administrator can input and/or can provide patient information such as, for example, height, weight, etc. Based on the user's height, the support system can be configured to calculate a predetermined and/or desired height or position (e.g., in the y-direction) of the patient attachment mechanism when attached to the tether and a harness worn by the user. In this manner, the predetermined and/or desired position of the patient attachment mechanism (e.g., a neutral position or "zero point") can be, for example, a reference point or the like against which a current position of the patient attachment mechanism can be compared. If, for example, the patient attachment mechanism is higher than the zero point, a level or amount of support may be reduced (e.g., to reduce an amount of tension in the tether and/or to otherwise allow for more "slack" in the tether) and/or the patient support system may be reset to define a new zero point. Conversely, if the patient attachment mechanism is below the zero point, a level or amount of support may be increased (e.g., to increase an amount of tension in the tether and/or to otherwise reduce an amount of slack in the tether).

In some instances, the support system can be configured to adjust and/or update the zero point during use. For example, in some instances, evaluating the amount of change in the tether length (or height of the patient attachment mechanism), the rate of change in the tether length, and/or a total duration of the change relative to the zero point can allow a patient to walk along a surface having a change in elevation or the like. For example, in some instances, the support system (or the electronic system thereof) can adjust and/or update the zero point or reference point in response to a relatively slow rate of change in the height and/or when the change is height is over a relatively long duration of time. In such instances, for example, the support system can determine that the patient is walking along a surface having a change in elevation and thus, can dynamically or actively adjust and/or update the "zero point" or reference point. Under such conditions, the support system can be configured to adjust and/or update the zero point prior to the amount of change in the tether length reaching and/or exceeding the fall limit or can adjust and/or update the zero point after the amount of change reaches and/or exceeds the fall limit. In other instances, the support system can provide support and/or can transition to a support configuration in response to an amount of change in the tether length reaching and/or exceeding the fall limit when the change in the height is at a relatively fast rate and/or when the change in height is over a relatively short time. In other words, the support system can provide support and/or can transition to the support configuration when the support system determines that the patient is falling rather than traveling along a surface having a change in elevation.

While the support system is described above as including and/or implementing a fall prevention system and/or method based on a distance or length of a portion of the tether (e.g., a fall limit or tolerance), in other embodiments, the support system can include and/or can implement a fall prevention system and/or method based on any suitable characteristic and/or parameter of the support system. For example, in some instances, the support system can be configured to receive an input from a user and/or clinician that is operable in placing the support system in an "active body control mode." In some instances, for example, the support system and/or the electronics assembly can receive an input operable in switching the support system from a "distance" or "fall limit mode" (see e.g., FIG. **60**) to the "active body control mode" (see e.g., FIG. **61**). That is to say, in some embodiments, a processor of the electronics assembly can be configured to execute a set of instructions and/or code (e.g., stored in the memory) to place the support system in the "fall limit mode" or in the "active body control mode."

In some embodiments, the active body control mode can be configured to dynamically support a portion of the patient's body weight based on, for example, a rate of change in the length of the tether (e.g., a velocity of the tether). In some instances, determining an amount of body weight to support based on a rate of change in the length of the tether can allow for a greater range of motion than when basing the amount of support on a length of the tether alone. Moreover, as described above with reference to the "distance" mode, the support system can be configured to evaluate a duration of the change in velocity to improve and/or tune a response of the support system.

As shown in FIG. **61**, in some embodiments, the support system can be programmed and/or set to provide a "Minimum" level of support (configured to provide the lowest level of fall prevention), a "Moderate" level of support (configured to provide a moderate amount or mid-level of fall prevention, greater than the minimum level), or a "Maximum" level of support (configured to provide the highest level of fall prevention, greater than the moderate level). In other embodiments, a support system can be configured to provide more than three levels of support (e.g., four, five, six, seven, eight, nine, ten, or more levels of support).

As described above, the level of support can be based on a rate of change in tether length over a predetermined time. That is to say, the level of support can be a function of the rate of change in tether length (or height of the patient attachment mechanism) and the overall duration (time) of the change in tether length. In some instances, the patient support system can be configured to determine a rate of change in a length of the tether based on, for example, an operating condition associated with the cam assembly and/or the winch assembly. In some instances, a relatively fast rate of change in tether length (as determined by an operating condition of the cam assembly, winch assembly, and/or any other suitable portion of the support system) can be indicative of a patient falling and thus, can result in the support system updating one or more operating conditions of the support system (e.g., trolley) to actively support a portion of the patient's body weight.

In some instances, setting the fall prevention system and/or method to the "Maximum" amount of support can be such that the support system provides support in response to a relatively low rate of change in the length of the tether (e.g., a relatively low velocity criterion and/or threshold). In some instances, setting the fall prevention system and/or method to the "Moderate" amount of support can be such that the support system provides support in response to a rate of change in the length of the tether that is greater than the rate of change when the system is set to the "Maximum" amount of support. In other instances, setting the fall prevention system and/or method to a "Minimum" amount of support can be such that the support system provides support in response to a rate of change in the length of the tether that is greater than the rate of change when the system is set to the "Moderate" amount of support. Moreover, by evaluating and/or determining a duration of the change in tether length, the support system can be configured to determine, for example, if a rate of change in the tether length is the result of a user changing his or her rate of walking or running, a result of the user rising to a standing position from a sitting position, a result of the user falling, etc.

In some instances, the fall prevention and/or level of support can be at least partially based on the duration of the rate of change. For example, in some instances, when a rate of change in the tether length reaches and/or exceeds a predetermined threshold the support system can be configured to determine a duration of the change in the tether length. In some instances, setting the fall prevention system to the "Maximum" support level can be such that a tolerance and/or threshold associated with the duration is less than a tolerance and/or threshold associated with the duration when the fall prevention system is set to the "Minimum" support level. As such, the support system can be configured to provide support and/or can be configured to transition to a support configuration in response to an increase in the rate of change in tether length (or height of the patient attachment mechanism) over a predetermined duration.

In some embodiments, the support system can be configured to update the level of support based on a patient's and/or user's performance against a predetermined program and/or metric (e.g., a timed-up-and-go test, a sit-to-stand test, a predetermined minimum walking speed, a predetermined number of falls within a given time, etc.). The level of support can be manually updated by a therapist, administrator, and/or user. In other instances, a user or administrator can define a set of criteria or the like (e.g., a number of falls, etc.), which if satisfied, results in the support system automatically updating the amount of support (e.g., increasing or decreasing the amount or level of support). Moreover, in some instances, the support system and/or the fall prevention system can have a default mode or the like associated with each test. For example, in some instances, it may be desirable to automatically place the fall prevention system in the "Active Body Control" mode such that support is based on a rate of change in the length of the tether rather than the "Distance" mode.

In some embodiments, the support system can be configured to "reset" the system after a fall or the like to place the patient attachment mechanism at the zero point. For example, in some instances, the support system and/or the fall prevention system can include and/or can perform an "Auto Recovery" as shown by the screen shot **905** in FIG. **63**. In such instances, the system can be configured to reset to a default and/or previous setting (e.g., to predetermined and/or default tether length) after a user falls. In addition, in some instances, the support system can provide support as the user recovers (e.g., stands up) after falling or the like.

While the fall prevention system is described above as being based on an amount of change in the tether length, a rate of change in the tether length, and a duration of the change in tether length, in other instances, the fall prevention system can be disabled, suspended, turned off, etc. For example, referring back to FIG. **62**, a screen shot **904**C

illustrates the fall prevention system in a "Disabled" mode. In such instances, it may be desirable to place the fall prevention system in the "Disabled" mode when preforming, for example, pre-gait and/or pre-use activities.

As described in detail above, the support system and/or the trolley can be configured to adjust one or more system parameters and/or operating conditions such that the trolley is maintained in a position substantially over-head of the user or patient. In some instances, the drive system of the trolley can be configured to move the trolley along the support track to maintain the trolley substantially over-head of the user or patient based on, for example, an angle of the tether or guide mechanism (e.g., the guide mechanism **2540**). In some embodiments, the support system can also account for patient movement in a direction perpendicular to an axis of the support track. That is to say, the support system can be configured to account for lateral patient movement and/or sway during gait.

In some embodiments, the trolley and/or at least a portion thereof can be configured to move in a side-to-side motion (lateral motion) in addition to moving along a length of the support track. For example, in some embodiments, the trolley and/or the guide mechanism can have one or more slides, suspension members, and/or the like configured to allow the trolley and/or the guide mechanism, respectively, to move in the lateral direction (as the trolley moves along the axis of the support track or when the trolley is in a stationary position in along the axis of the support track). In this manner, the trolley or a portion thereof, can move with 2-degrees of freedom to maintain the tether in a position substantially over-head of the patient and/or patient attachment mechanism (e.g., extending at a 90° angle or substantially vertically from the trolley).

In other embodiments, the trolley and/or a portion thereof can include one or more sensors, encoders, gyroscopes, etc. configured to sense and/or determine an amount of side-to-side motion (lateral motion). For example, in some instances, the guide mechanism or the like can be configured to pivot about two axes and can include one or more sensors, gyroscopes, encoders, etc. configured to sense and/or determine a pivot position, velocity, and/or acceleration about each axis. In other words, the guide mechanism can allow for forward and aft movement (pivoting) as well as side-to-side movement (pivoting) and can include and/or can be operably coupled to one or more sensors or the like configured to sense and/or detect movement in each direction (e.g., a 2-degree of freedom sensor or the like). Thus, the angular position, velocity, and/or acceleration of the tether and/or guide mechanism in each direction can be determined and/or sensed and data received from the sensor or the like can be used along with data from the other sensors and/or encoders (described above) to determine and/or update one or more operating conditions of the patient support system.

As described above, the support system can include any suitable number of sensors, encoders, gyroscopes, transducers (e.g., force transducers), and/or the like (collectively referred to herein as "sensors"). The electronic system of the support system can receive data from the sensors and can determine and/or update one or more operating conditions of the support system to provide a predetermined and/or desired level or amount of support for the user or patient. In some instances, the data received from the sensors can be compared against predetermined and/or standard values or levels and errors therebetween can be used to determine an amount of dynamic and/or active body weight support.

Any of the patient support systems and/or body weight support systems can be used in conjunction with and/or can include any other suitable device configured to be used during a patient's gait or gait training. In some embodiments, such a device can be a secondary training device, an electronic device or computer, an orthosis or gait assist device, a moving platform, surface, or walkway (e.g., treadmill or the like), and/or any other suitable device. For example, a patient support system can include camera, infrared emitter and receiver, a visual light source and sensor, magnetic sensor, a force and/or pressure plate and sensor, and/or the like. In some embodiments, a patient support system can include, for example, a projector configured to project a graphical representation of data associated with a predetermined track or path along which the patient is to walk. In some instances, such a projector can project images such as stop signs, turn signs, obstacles to walk around, etc.). Moreover, in some instances, a patient reaching a target location projected onto a surface by the projector can be associated with a value or the like (e.g., a relatively high value) used to determine a patient performance score. On the other hand, failing to avoid an obstacle and/or failing to follow a predetermined path projected onto a surface by the projector can be associated with a value, score, and/or the like (e.g., a relatively low value). In some instances, such a projector can project a hologram of the patient walking so that they may see themselves walking either from the front or behind.

In some embodiments, the patient support systems and/or the body weight support systems can be used while a user (or patient) walks along and/or otherwise moves relative to any suitable surface. In some instances, for example, the user can walk along and/or move relative to a surface that is stationary beneath the user's feet as the user stands, walks, runs, etc. Such a stationary surface can be, for example, the floor, the ground, a platform, and/or any other suitable surface. Moreover, the stationary surface can be substantially flat or can be inclined or declined (e.g., a set of steps, a ramp, etc.). In other instances, the user can walk along and/or move relative to a surface that is not stationary beneath the user's feet as the user stands, walks, runs, etc. Said another way, the patient support systems and/or body weight support systems described herein can be used to support at least a portion of a user's weight as the user moves relative to and/or walks on a surface, which in turn, moves beneath the user's feet as the user moves, walks, runs, etc. The moving surface can be any surface such as, for example, a moving surface (belt) of a treadmill, a moving balance platform, and/or the like.

In embodiments in which a support system supports a user as the user is on or moves relative to the moving surface of a treadmill, an electronic device of the patient support system can receive data associated with one or more operating conditions of the treadmill and can use the data associated with the treadmill and data associated with the operating conditions of the patient support system to provide gait training for the user utilizing the treadmill, define one or more gait characteristics of the user, provide an analysis of data and/or information associated with the gait training or one or more training sessions, and/or the like. Moreover, the patient support system and/or any suitable electronic device can be configured to graphically represent data and/or information associated with the treadmill, the patient support system, and/or one or more gait training sessions on a display of the device.

For example, FIGS. **64-69** are screenshots **910-915**, respectively, illustrating graphical representations of data associated with a support system being used in conjunction with a treadmill. As shown in FIGS. **64-66**, the patient support system and/or the electronic device can present data

associated with the trolley such as, for example, operating mode, an amount or level of dynamic unloading, a maximum change in tether length prior to providing support, any suitable session data or information (e.g., total running time, distance travel, walking speed, number of falls or number of falls prevented, tether position, etc.), and/or any other suitable data. In some instances, for example, the patient support system and/or the electronic device can graphically represent data similar to the data represented by the screenshots **904** and **904**A, shown in FIGS. **59** and **60**, respectively.

In addition to data associated with the trolley, the support system and/or electronic device can be configured to graphically represent data associated with the treadmill. For example, as shown in the screenshots **910** (FIG. **64**), **911** (FIG. **65**), **912** (FIG. **66**), and **913** (FIG. **67**), the support system and/or the electronic device can graphically represent data and/or controls associated with the treadmill. In some instances, the data graphically represented on the display can provide a user interface allowing a user to select and/or control one or more operating settings of the treadmill such as, for example, belt speed, incline, and/or the like. In other instances, the user can, for example, initiate a pairing or syncing of the treadmill with the trolley; start, stop, or pause operation of the treadmill (including an emergency stop); change the direction of the belt; change an incline or decline of the belt or treadmill; and/or the like. In some instances, the support system and/or the electronic device can be configured to control one or more operating conditions of the trolley based on data associated with one or more operating conditions of the treadmill and vice versa. For example, in some instances, the support system and/or the electronic device can be configured to stop the treadmill (e.g., stop the movement of the belt) in response to determining the user has fallen based on data associated with one or more operating conditions of the trolley. For example, in some instances, the trolley (and/or an electronic device in communication with the trolley) can determine a user has fallen based at least in part on a rapid or sudden change in a force exerted by the user on the tether and/or a rapid or sudden increase in a length of at least a portion of the tether. Thus, in some such instances, the support system, electronic device, and/or controller can be configured to stop or pause the operation of the treadmill based on determining that the user has fallen. Moreover, the system can resume the operation or movement of the trolley in response to determining that the user has recovered from the fall (e.g., is in a desired standing, walking, or neutral position).

In some embodiments, the electronic device configured to graphically represent data associated with the trolley and the treadmill can be the same electronic device that controls both the trolley and the treadmill. In such embodiments, the electronic device can receive signals from one or more sensors, motors, controllers, etc. and can perform one or more processes on data received via such signals. In other embodiments, an electronic device can be configured to graphically represent data and/or information associated with the trolley and the treadmill based on one or more signals received from an electronic device or a controller of the trolley and/or based on or more signals received from an electronic device or a controller of the treadmill. In other words, in some embodiments, an electronic device can be configured to receive and aggregate one or more analyzed or at least partially processed data sets from one or more components of the support system and can graphically represented the aggregated data on a display. Said another way, any of the support systems described herein can include a centralized electronic device and/or controller configured to control one or more components of the support system or can include a decentralized or distributed network of electronic devices and/or controllers. Moreover, in embodiments in which the support system includes a decentralized or distributed network of electronic device and/or controllers, the support system can include at least one electronic device and/or controller configured to compile and/or aggregate data received from one or more components of the support system and to graphically represent such compiled or aggregated data on a display.

As described above, the support system and/or electronic device in communication therewith can be configured to determine and/or define one or more characteristics associated with the user's gait based on data associated with the support system (e.g., the trolley) and any suitable device being used with the support system (e.g., the treadmill). For example, the screenshot **914** shown in FIG. **68** is an example of a session summary that can provide data and/or information associated with a user session or the like. Such data and/or information can include, for example, the date and time of the session; the total training time; a minimum, maximum, and/or average walking speed; a minimum, maximum, and/or average amount of unloading or support; a total distance traveled; a total number of falls or a total number of falls prevented; and/or any other suitable data and/or information. Moreover, the user or clinician can provide notes, information, data, and/or input that can be associated and/or stored with the session data. As illustrated by the screenshot **915** of FIG. **69**, the support system and/or electronic device can also be configured to define and display one or more graphs, plots, charts, etc. representing data associated with one or more user sessions. For example, as shown in FIG. **69**, the support system and/or electronic device can define and display a graph illustrating a user fall profile during one or more sessions, a user speed and distance graph, and/or any other suitable graph, chart, and/or representation of data associated with one or more user sessions.

Any of the patient support systems and/or body weight support systems can be used with any suitable track and/or power rail such as those described herein. In some embodiments, a patient support system can include a track and/or power rail configured to allow for switching, diverting, and/or redirecting of a trolley movably coupled thereto. For example, FIG. **70** illustrates a first track portion **9620**A and a second track portion **9620**B, and a first power rail portion **9050**A and a second power rail portion **9050**A. In this embodiment, the first track portion **9620**A and the second track portion **9620**B are disposed perpendicular to each other. Similarly, the first power rail portion **9050**A and the second power rail portion **9050**B are disposed perpendicular to each other.

As shown in FIG. **70**, a turntable **9625** includes a third track portion **9620**C and a third power rail portion **9050**C. The turntable **9625** is configured to be rotated relative to the track portions **9620**A and **9620**B and the power rails **9050**A and **9050**B, as indicated by the arrow AA. For example, in some embodiments, the turntable **9625** can be manually turned (e.g., a user exerts a force on a portion of the turntable **9625** such as a handle or the like (not shown in FIG. **70**)). In other embodiments, the turntable **9625** can include a motor or the like (not shown in FIG. **70**) that can receive a signal from a controller or the like and based on that signal, can rotate the turntable **9625**. Therefore, in use, the turntable **9625** can rotate to a position relative to the track portions **9620**A and **9620**B and the power rails **9050**A and **9050**B to place the third track portion **9620**C in line with the first track

portion **9620**A, and to place the third power rail portion **9050**C in line with the first power rail portion **9050**A, as shown in FIG. **70**. More particularly, when the third track portion **9620**C is placed in line with the first track portion **9620**A, the first track portion **9620**A and the third track portion **9620**C collectively form a substantially continuous track along which a trolley can move.

Similarly, the first power rail portion **9050**A and the third power rail portion **9050**B can collectively form a substantially continuous power rail configured to power the trolley suspended from the track, collectively formed by the first track portion **9620**A and the third track portion **9620**C. Specifically, in this embodiment, the turntable **9625** can be disposed in a position such that the first power rail portion **9050**A and the third power rail **9050**C are in electric communication. Thus, an electric current can flow from a power source (not shown), along a first length of the first power rail portion **9050**A, along the third power rail portion **9050**C, and along a second length of the first power rail portion **9050**A. Moreover, in some embodiments, the ends of the power rail portions **9050**A, **9050**B, and **9050**C can include a transfer section or the like (e.g., a flared or flanged end) that can allow for a given amount of misalignment between the first power rail portion **9050**A or the second power rail portion **9050**B and the third power rail portion **9050**C.

In use, a user (e.g., a patient, a therapist, a technician, a doctor, etc.) may want to redirect a trolley disposed along, for example, a length of the first track portion **9620**A. As such, the user can cause the trolley to move from a position along the first track portion **9620**A to a position along the third track portion **9620**C. With the trolley suspended from the third track portion **9620**C and with the trolley in electrical communication with the third power rail **9050**C, the user can rotate (e.g., either manually or electrically) the turntable **9625** to a position in which the third track portion **9620**C is substantially in line with the second track portion **9620**B and in which the third power rail portion **9050**C is in line with the second power rail portion **9050**B. When the third track portion **9620**C is substantially aligned with the second track portion **9620**B and the third power rail portion **9050**C is substantially aligned with the second power rail portion **9050**B, the user can cause the trolley to move from the position along the third track portion **9620**C to a position along the second track portion **9620**B. In this manner, the trolley can be turned, switched, rotated, and/or otherwise redirected. Similarly stated, the turntable can be rotated from a first position to a second position to rotate, switch, turn, and/or otherwise redirect the trolley.

While the patient support system **2000** is described above as including the power rail **2620** configured to provide electrical power to the trolley **2100**, in other embodiments, a patient support system can include any suitable power system. For example, FIG. **71** is a schematic illustration of a body weight support system **10000** according to an embodiment. The body weight support system **10000** (also referred to herein as "support system") can be substantially similar in form and/or function to any of the support systems described herein. For example, the support system **10000** includes a trolley **10100** movably suspended from a support track **10050**. The support track **10050** and the trolley **10100** can be substantially similar to the support track **2050** and trolley **2100**, respectively, described above with reference to FIGS. **2-34**. Thus, the support track **10050** and the trolley **10100** are not described in further detail herein.

The support system **10000** can differ from the support system **2000**, however, in the arrangement of the power system **10600**. For example, the support system **2000** includes a power rail **2620** that is substantially parallel to the support track **2050** and that is in electrical communication with the trolley **2100** to provide electric power thereto, as described above. In the embodiment shown in FIG. **71**, however, the power system **10600** includes a central power source and/or supply **10610** and a power rail **10620** configured to rotate relative to the power source **10610** in response to a movement of the trolley **10100** along the support track **10050**, as indicated by the arrow C in FIG. **71**. For example, in some embodiments, the power rail **10620** can be a telescoping power rail or the like having a length that is configured to extend or retract (as indicated by the arrow D in FIG. **71**) as the trolley **10100** moves along the support track **10050**. In other embodiments, the power rail **10620** can be a flexible and/or extendable cable or the like. In this manner, the power rail **10620** can pivot about the power source **10610**, to provide substantially continuous electrical power as the trolley **10100** moves along the support track **10050**. While the support track **10050** is particularly shown in FIG. **71**, it should be understood that the power system **10600** can be used with a support track **10050** having any suitable shape. For example, the power system **10600** can be used with a linear or straight support track, an oval or circular support track, and/or a support track having an irregular shape. That is to say, the rotatable and telescoping arrangement of the power rail **10620** can allow the power system **10600** to be used with any suitable support track having any suitable shape.

The power rail **10620** can include any suitable power conductor, surface, wire, and/or the like. For example, in some embodiments, the power rail **10620** can include one or more inner conductive surfaces similar to the power rail **2620**. In other embodiments, the power rail **10620** can be a conduit or the like configured to house a power cable or wire (and/or any suitable electronic communication cable or wire). In still other embodiments, the power rail **10620** can be any suitable tether or the like configured to conduct and/or transmit electric power. By way of example, FIG. **72** illustrates a power rail **11620** according to an embodiment. In such embodiments, the power rail **11620** is a substantially hollow tube including and/or having at least one conductive inner surface **11621**. As such, a collector **11770** and/or any other suitable conductive portion of a trolley or support system can be at least partially disposed within the power rail **11620** to place the collector **11770** (or conductor of the trolley) in electric contact with the conductive inner surface **11621** of the power rail **11620**, as described in detail above with reference to the support system **2000**.

Alternatively, FIG. **73** illustrates a power rail **12620** according to a different embodiment. As shown, the power rail **1620** is a substantially flat or otherwise unenclosed power rail **1620** having at least one conductive surface **12621** that is substantially open or exposed. In such embodiments, a collector **12770** and/or any suitable conductive portion of a trolley or support system can be disposed adjacent to and/or otherwise can be positioned such that the collector **12770** (or conductor of the trolley) is in electric contact with the exposed and/or otherwise available conductive surface **12621** of the power rail **12620**. In some embodiments, such an arrangement can allow, for example, the power rail **12620** to be coupled to and/or integrated with a support track (not shown in FIG. **73**) along which the trolley moves. In other embodiments, the power rail **12620** can be offset from a support track as described, for example, with reference to the support system **2000**.

While the power rails **2620**, **10620**, **11620**, and/or **12620** are specifically described above as being independent of a corresponding support track, in other embodiments, a support track can include one or more conductive surfaces and/or members configured to supply electric power to a portion of a trolley suspended therefrom. Moreover, while the power rails **2620**, **10620**, **11620**, and **12620** are described above as providing electric power to the respective support systems, in some embodiments, a support system can include one or more batteries, battery systems, capacitors, energy storage devices, uninterruptible power supplies (UPS), and/or the like configured to store and/or provide electric power to one or more components or devices of the support system. For example, as described above, a support system can include a UPS electrically connected in any suitable position and/or configuration within the support system to provide a primary or a backup flow of electric power to one or more components or devices (e.g., a power supply, a trolley, a compute device, a controller, a secondary training device such as a treadmill, etc.). Thus, such a UPS (or any other suitable form of energy storage or backup device) can be configured to provide uninterrupted electric power to the support system and/or at least a portion thereof.

While various embodiments have been described above, it should be understood that they have been presented by way of example only, and not limitation, and as such, various changes in form and/or detail may be made. For example, while the trolley **2100** is described above with reference to FIGS. **2-33** as having a particular shape, size, and/or configuration, it should be understood that changes in size, shape, configuration, and/or arrangement of one or more components can be made without altering the functionality thereof. By way of example, FIGS. **74-76** illustrate a trolley **12100** according to an embodiment. The trolley **12100** can be substantially similar in form and/or function to the trolley **2100** described above with reference to FIGS. **2-33**. For example, the trolley **2100** includes a drive system **12300** configured to movably suspend the trolley **12100** from a support track (not shown in FIGS. **74-76**) and a support mechanism **12500** that includes a tether **12505** configured to attach to a harness or the like worn by a user to couple the user to the support mechanism **12500**. In this embodiment, the drive system **12300** and the support mechanism **12500** can be substantially similar in at least form and/or function to the drive system **2300** and support mechanism **2500**, respectively, of the trolley **2100**.

The trolley **12100** shown in FIGS. **74-76** can differ from the trolley **2100** shown in FIGS. **2-33**, however, by including a cover **12260** having a size, shape, and/or configuration that is different from the cover **2260** of the trolley **2100**. For example, the cover **12260** defines a notch **12267** configured to receive a portion of the support mechanism **12500** (e.g., a portion of a cam assembly or the like), as shown in FIGS. **74** and **75**. In addition, the cover **12260** defines an opening **12266** through which at least a portion of the tether **12505** can extend to allow an end portion of the tether **12505** to be coupled to a patient attachment mechanism and/or harness worn by the user and/or patient, as shown in FIG. **76**. Accordingly, while the cover **12260** shown in FIGS. **74-76** varies in shape, size, and/or configuration from the cover **2260** (see e.g., FIGS. **4-9**), the covers **2260** and **12260** can function in a substantially similar manner to enclose, cover, and/or house at least a portion of the trollies **2100** and **12100**, respectively.

As another example, while the attachment mechanism **2800** is described above with reference to FIG. **34** as including energy storage members **2850**, in other embodiments, an attachment mechanism need not include an energy storage member. In such embodiments, the attachment mechanism can be coupled to, for example, the trolley **2100** and the further coupled to a harness or the like worn by a patient. In such embodiments, the trolley **2100** can function in a substantially similar manner as described above.

Although the trolley **2100** is described above with reference to FIGS. **2-33** as including a motorized drive system **2300** and an active support mechanism **2500**, in other embodiments, a trolley can include either a motorized drive system or an active support mechanism. Similarly stated, the drive system **2300** and the support mechanism **2500** can be mutually exclusive and can independently function in a similar manner to those described above.

Any portion of the apparatus and/or methods described herein may be combined in any suitable combination, unless explicitly expressed otherwise. For example, in some embodiments, the patient support mechanism **2500** of the trolley **2100** included in the support system **2000** can be replaced with a system similar to the support system **3900**. In such embodiments, a cylinder, a piston, and an energy storage member can extend, for example, from the base **2210** of the housing **2200** of the trolley **2100**. Expanding further, the kinetic and potential energy of the energy storage member (e.g., storage member **3960**) could be actively controlled via a feedback system similar to the system described above with reference to the trolley **2100**. For example, the energy storage member **3960** could be compressed air, the pressure of which could be controlled in response to a force exerted on the piston.

Any of the systems and/or devices described herein can be used in any suitable method to provide support to a user, for example, during gait training and/or the like. For example, FIG. **77** is a flowchart illustrating a method **10** of using a body weight support system according to an embodiment. The body weight support system can be similar to any of the support systems described herein. In some embodiments, for example, the support system can be substantially similar to the support system **2000** described in detail above with reference to FIGS. **2-33**. As such, the support system can include a trolley (e.g., similar to the trolley **2100**) or the like configured to be movably suspended from a support track. The support system can include a patient support mechanism (e.g., similar to the support mechanism **2500**) that has a tether configured to be coupled to an attachment device worn by or otherwise coupled to a user. As such, coupling the tether to the attachment device, in turn, can couple the user to the body weight support system and/or at least the trolley included therein.

The method **10** includes defining a reference length of the tether when the tether is coupled to the attachment device and the attachment device is in an initial position, at **11**. For example, as described above with reference to FIGS. **59** and **60**, a user, therapist, trainer, etc. can input, provide, and/or otherwise define a "zero point" or reference point associated with a neutral position of the attachment device, which in turn, is associated with and/or corresponds to a determined or determinable length of the tether. In addition, the user, therapist, trainer, etc. can provide an input, selection, instruction, etc. operable to cause the support system to define a threshold length of the tether, at **12**.

As described in detail above, the body weight support system is configured to support at least a portion of the user's weight during use (e.g., gait training). As shown in FIG. **77**, the method **10** includes providing a first amount of body weight support during the gait training as the user moves relative to and/or on a surface (e.g., the floor or

ground, or along or on a training device such as a treadmill) and the length of the tether is less than the threshold length of the tether, at **13**. For example, as described above, the first amount of body weight support can be an amount of support provided to the user when the user is standing, walking, running, and/or otherwise not actively falling. In some embodiments, the first amount of body weight support can be, for example, zero support. That is to say, the tether can couple the user to the body weight support system but, in some instances, the body weight support system may not provide support unless the user is falling and/or unless the system is otherwise engaged to do so. In other embodiments, the first amount of support can be a non-zero portion of the user's weight including, for example, some or substantially all of the user's weight.

A second amount of body weight support is provided during the gait training as the user moves relative to and/or on the surface and the length of the tether is greater than the threshold length of the tether, at **14**. For example, as described above, the body weight support system can be configured to respond, react, and/or otherwise support a user in response to a change in force applied by the user on the tether, in response to the user moving relative to the body weight support system, in response to the user falling, and/or the like. More particularly, in this example, the body weight support system can be configured to provide the second amount of body weight support in response to a change (e.g., an increase) in the length of the tether such that the length is greater than the threshold length. That is to say, the body weight support system can be configured to provide the second amount of body weight support in response to the user falling.

The method **10** further includes displaying data associated with the gait training on a display of an electronic device included in the body weight support system, at **15**. For example, as described above with reference to FIGS. **50-69**, the body weight support system can be configured present data in the form of graphs, charts, user interfaces, etc. that can provide a user and/or a therapist or trainer with information regarding one or more training sessions (as described in detail above). Accordingly, the user, therapist, trainer, etc. can review the data to determine, for example, one or more characteristics associated with the user's gait and/or his or her performance, improvement, deficits, strengths, etc. during the gait training.

FIG. **78** is a flowchart illustrating a method **20** of using a body weight support system according to another embodiment. The body weight support system can be similar to any of the support systems described herein (e.g., the support system **2000** described in detail above with reference to FIGS. **2-33**). As such, the support system can include a trolley (e.g., similar to the trolley **2100**) or the like configured to be movably suspended from a support track. The support system can include a patient support mechanism (e.g., similar to the support mechanism **2500**) that has a tether configured to be coupled to an attachment device worn by or otherwise coupled to a user. As such, coupling the tether to the attachment device, in turn, can couple the user to the body weight support system and/or at least the trolley included therein.

The method **20** includes defining a reference length of the tether when the tether is coupled to the attachment device and the attachment device is in an initial position, at **21**. For example, as described above with reference to FIGS. **59** and **60**, a user, therapist, trainer, etc. can input, provide, and/or otherwise define a "zero point" or reference point associated with a neutral position of the attachment device, which in turn, is associated with and/or corresponds to a determined or determinable length of the tether. In addition, the user, therapist, trainer, etc. can provide an input, selection, instruction, etc. operable to cause the support system to define a first criterion associated with a change in a length of the tether, at **22**; can provide an input, selection, instruction, etc. operable to cause the support system to define a second criterion associated with a change in a length of the tether, at **23**; and can provide an input, selection, instruction, etc. operable to cause the support system to define an amount of bodyweight support to provide in response to the user falling during the gait training, at **24**. For example, in some embodiments, the first criterion can be a rate of change in the length of the tether and the second criterion can be a duration of the change in the length of the tether. In other embodiments, the first criterion and the second criterion can be any suitable criteria(ion). The amount of body weight to support can be any suitable portion of the user's body weight. In some instances, for example, the amount of body weight support can be expressed as a percentage of the user's weight (e.g., 0%, 10%, 20%, 30%, etc.). In other instances, the amount of the body weight support can be expressed as a weight term (e.g., in pounds or kilograms).

The method **20** includes determining whether a fall has occurred based on the first criterion and the second criterion being satisfied, at **25**. For example, during gait training, the user may move relative to and/or walk on a surface, which in turn, can result in a change in force exerted on the tether (as described in detail above). In some instances, the user falling during gait training can result in an increase in the force exerted by the user on the tether that results in a relatively high rate of change in a length of at least a portion of the tether, which in turn, can be sufficient to satisfy the first criterion. In some instances, however, a similar rate of change in the length of the tether may result from the user's movement when not falling (e.g., if the user sits down or stands up, bends down, ascends or descends a ramp, stairs, or platform, and/or the like). Thus, to avoid falsely defining or falsely determining the occurrence of a fall, the support system can be configured such that a fall is defined and/or determined in response to satisfying both the first criterion (e.g., the rate of change in the length of the tether) and the second criterion (e.g., a duration of the change in the length of the tether or the amount of time it takes for the change in the length of the tether). Furthermore, the amount of body weight support can be provided when the first criterion and the second criterion are satisfied, at **26**.

FIG. **79** is a flowchart illustrating a method **30** of using a body weight support system according to another embodiment. The body weight support system can be similar to any of the support systems described herein (e.g., the support system **2000** described in detail above with reference to FIGS. **2-33**). As such, the support system can include a trolley (e.g., similar to the trolley **2100**) or the like configured to be movably suspended from a support track. The support system can include a patient support mechanism (e.g., similar to the support mechanism **2500**) that has a tether configured to be coupled to an attachment device worn by or otherwise coupled to a user. As such, coupling the tether to the attachment device, in turn, can couple the user to the body weight support system and/or at least the trolley included therein.

The method **30** includes defining a reference length of the tether when the tether is coupled to the attachment device and the attachment device is in an initial position, at **31**. For example, as described above with reference to FIGS. **59** and **60**, a user, therapist, trainer, etc. can input, provide, and/or

otherwise define a "zero point" or reference point associated with a neutral position of the attachment device, which in turn, is associated with and/or corresponds to a determined or determinable length of the tether. In addition, the user, therapist, trainer, etc. can provide an input, selection, instruction, etc. operable to cause the support system to define a threshold length of the tether that is associated with and/or otherwise is indicative of the user falling during the gait training, at **32**; and can provide an input, selection, instruction, etc. operable to cause the support system to define a threshold number of falls during the gait therapy, at **33**.

The method **30** includes providing a predetermined amount of body weight support during the gait training as the user moves relative to and/or on a surface (e.g., the floor or ground, or relative to or on a training device such as a treadmill) and the number of falls is less than the threshold number of falls, at **34**. For example, as described above, the predetermined amount of body weight support can be an amount of support provided to the user when the user is standing, walking, running, and/or otherwise not actively falling. In some embodiments, the first amount of body weight support can be, for example, zero support. That is to say, the tether can couple the user to the body weight support system but, in some instances, the body weight support system may not provide support unless the user is falling and/or unless the system is otherwise engaged to do so. In other embodiments, the first amount of support can be a non-zero portion of the user's weight including, for example, some or substantially all of the user's weight (e.g., expressed or represented as a percentage of the user's weight or as a weight value in pounds or kilograms).

In some instances, the predetermined amount of body weight support provided to the user during the gait training is increased in response to the threshold number of falls being met, at **35**. For example, in some instances, repeated falls by the user may indicate that the user would benefit from more body weight support. Thus, the body weight support system can increase the amount of support provided to the user. In some instances, the amount of increase can be predetermined increase in the amount of support (e.g., a 1% increase, a 5% increase, a 10% increase, a 20% increase, etc.). In other instances, the amount of increase can be calculated based on characteristics associated with the user's performance during the gait training. In sill other instances, the amount of increase can be input by the user, therapist, trainer, etc.

The method **30** further includes displaying data associated with the gait training on a display of an electronic device included in the body weight support system, at **35**. For example, as described above with reference to FIGS. **50-69**, the body weight support system can be configured present data in the form of graphs, charts, user interfaces, etc. that can provide a user and/or a therapist or trainer with information regarding one or more training sessions (as described in detail above). Accordingly, the user, therapist, trainer, etc. can review the data to determine, for example, one or more characteristics associated with the user's gait and/or his or her performance, improvement, deficits, strengths, etc. during the gait training.

Where methods and/or schematics described above indicate certain events and/or flow patterns occurring in certain order, the ordering of certain events and/or flow patterns may be modified. Additionally, certain events may be performed concurrently in parallel processes when possible, as well as performed sequentially.

Some embodiments described herein relate to a computer storage product with a non-transitory computer-readable medium (also can be referred to as a non-transitory processor-readable medium) having instructions or computer code thereon for performing various computer-implemented operations. The computer-readable medium (or processor-readable medium) is non-transitory in the sense that it does not include transitory propagating signals (e.g., propagating electromagnetic wave carrying information on a transmission medium such as space or a cable). The media and computer code (also referred to herein as code) may be those designed and constructed for the specific purpose or purposes. Examples of non-transitory computer-readable media include, but are not limited to: magnetic storage media such as hard disks, optical storage media such as Compact Disc/Digital Video Discs (CD/DVDs), Compact Disc-Read Only Memories (CD-ROMs), magneto-optical storage media such as optical disks, carrier wave signal processing modules, and hardware devices that are specially configured to store and execute program code, such as Application-Specific Integrated Circuits (ASICs), Programmable Logic Devices (PLDs), Read-Only Memory (ROM) and Random-Access Memory (RAM) devices. Other embodiments described herein relate to a computer program product, which can include, for example, the instructions and/or computer code discussed herein.

Examples of computer code include, but are not limited to, micro-code or micro-instructions, machine instructions, such as produced by a compiler, code used to produce a web service, and files containing higher-level instructions that are executed by a computer using an interpreter. For example, embodiments may be implemented using imperative programming languages (e.g., C, FORTRAN, etc.), functional programming languages (Haskell, Erlang, etc.), logical programming languages (e.g., Prolog), object-oriented programming languages (e.g., Java, C++, etc.), or other programming languages and/or other development tools. Additional examples of computer code include, but are not limited to, control signals, encrypted code, and compressed code.

What is claimed is:

1. A method of using a body weight support system to provide body weight support during gait training, the body weight support system including a drive assembly configured to movably suspend the body weight support system from a support track and a tether configured to be coupled to an attachment device worn by a user to couple the user to the body weight support system, the method comprising:

defining a reference length of the tether when the attachment device is in an initial position;

defining a threshold length of the tether;

providing a first amount of body weight support during the gait training as the user moves relative to a surface and the length of the tether is less than the threshold length of the tether;

providing a second amount of body weight support during the gait training as the user moves relative to the surface and the length of the tether is greater than the threshold length of the tether, the drive assembly configured to move the body weight support system relative to the support track to maintain the body weight support system in a substantially overhead position relative to the user as the user moves relative to the surface; and

displaying data associated with the gait training on a display of an electronic device included in the body weight support system.

2. The method of claim 1, wherein the length of the tether is increased in response to an increase in force exerted by the user on the tether.

3. The method of claim 2, wherein the increase in the force exerted by the user on the tether is associated with the user falling during the gait training.

4. The method of claim 1, wherein the surface relative to which the user moves is a stationary surface.

5. The method of claim 1, wherein the surface relative to which the user moves is a moving surface included in a treadmill.

6. The method of claim 5, wherein displaying the data associated with the gait training on the display includes displaying data associated with an operating condition of the body weight support system and an operating condition of the treadmill.

7. A method of using a body weight support system to provide body weight support during gait training, the body weight support system including a tether configured to be coupled to an attachment device worn by a user to couple the user to the body weight support system, the method comprising:

defining a reference length of the tether when the attachment device is in an initial position;

defining a first criterion associated with a change in a length of the tether;

defining a second criterion associated with a change in a length of the tether;

defining an amount of the body weight support to provide in response to the user falling during the gait training;

maintaining the body weight support system in a substantially overhead position relative to the user as the user moves relative to a surface;

determining a fall has occurred based on the first criterion and the second criterion being satisfied; and

providing the amount of body weight support in response to the first criterion and the second criterion being satisfied.

8. The method of claim 7, wherein the first criterion is a rate of change in the length of the tether.

9. The method of claim 7, wherein the second criterion is a duration during which the length of the tether is changed.

10. The method of claim 9, wherein the second criterion is a minimum duration.

11. The method of claim 7, wherein the first criterion is a rate of change in the length of the tether, the second criterion is a duration during which the length of the tether is changed, and the amount of body weight support provided in response to the first criterion and the second criterion being satisfied is a first amount of body weight support, the method further comprising:

providing a second amount of body weight support when at least one of the first criterion or the second criterion is not satisfied, the second amount of body weight support being less than the first amount of body weight support.

12. The method of claim 7, further comprising:

redefining the reference length of the tether in response to a change in the length of the tether that does not satisfy at least one of the first criterion or the second criterion.

13. A method of using a body weight support system to provide body weight support during gait training, the body weight support system including tether configured to be coupled to an attachment device worn by a user to couple the user to the body weight support system, the method comprising:

defining a reference length of the tether when the attachment device is in an initial position;

defining a threshold length of the tether, the threshold length of the tether being associated with the user falling during the gait training;

defining a threshold number of falls during the gait training;

providing a predetermined amount of body weight support during the gait training as the user moves relative to a surface and the number of falls is less than the threshold number of falls;

increasing the predetermined amount of body weight support to be provided to the user during the gait training in response to the threshold number of falls being met; and

displaying data associated with the gait training on a display of an electronic device included in the body weight support system.

14. The method of claim 13, wherein the surface relative to which the user moves is a stationary surface.

15. The method of claim 14, wherein the body weight support system includes a drive assembly configured to movably suspend the body weight support system from a support track, the drive assembly configured to move the body weight support system relative to the support track in response to the user moving relative to the surface such that the body weight support system is maintained in a substantially overhead position relative to the user.

16. The method of claim 13, wherein the surface relative to which the user moves is a moving surface included in a treadmill.

17. The method of claim 16, wherein displaying the data associated with the gait training on the display includes displaying data associated with an operating condition of the body weight support system and an operating condition of the treadmill.

18. The method of claim 13, wherein providing the predetermined amount of body weight support during the gait training as the user moves relative to the surface is in response to a length of the tether exceeding the threshold length of the tether.

19. The method of claim 13, wherein the reference length of the tether is a first reference length of the tether, the method further comprising:

defining a second reference length of the tether in response to the threshold number of falls being met, the second reference length of the tether being shorter than the first reference length of the tether.

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