

Claims:

1. A device (1) for rehabilitation of the upper limb, comprising:
 - a frame (11); and
 - an exoskeleton (12) mounted on the frame (11), the exoskeleton
- 5 (12) including:
 - a first joint (121) coupled to the frame (11), the first joint (121) configured to be situated above a shoulder of a human subject and having a first axis of rotation substantially coinciding with the horizontal abduction/adduction rotation axis
 - 10 (I) of the shoulder of the human subject;
 - a second joint (122) configured to be situated behind the shoulder of the human subject and having a second axis of rotation coinciding with the abduction/adduction rotation axis (II) of the shoulder of the human subject;
 - 15 a first L-shaped connector (123) that connects the first joint (121) to the second joint (122);
 - a third joint (124) configured to be situated at the side of the shoulder of the human subject and having a third axis of rotation substantially coinciding with the flexion/extension
 - 20 rotation axis (III) of the shoulder of the human subject;
 - a second L-shaped connector (125) that connects the second joint (122) to the third joint (124); and
 - at least one attaching means (126) for attaching at least a part of the upper limb of the human subject to the exoskeleton
 - 25 (12).
2. The device (1) according to claim 1, wherein the exoskeleton (12) further includes a telescopic link (128) coupled to the third joint (124), and an elbow joint (127) coupled to the third joint (124) and
- 30 having a fourth axis of rotation substantially coinciding with the flexion/extension rotation axis (IV) of an elbow of the human subject.
3. The device (1) according to claim 1, wherein at least one of the first joint (121), the second joint (122), the third joint (124), and
- 35 the elbow joint (127), is a motor-driven actuator.
4. The device according to claim 1, wherein the first L-shaped

FIG. 4

