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| **Authors** | **Parameters** | **Thresholds** | **Algorithm’s rationale** |
| ***Chen et al.*** | (1) | >3 gSet arbitrarily based on empirical data (>20°) | IMPACT DETECTION+CHANGE IN ORIENTATION |
| ***Kangas et al. (1a)*** | (2) | >2 g<0.5 g | IMPACT DETECTION+POSTURE MONITORING |
| ***Kangas et al. (1b)*** | (3) | >1.7 g<0.5 g | IMPACT DETECTION+POSTURE MONITORING |
| ***Kangas et al. (1c)*** |  | >2 g<0.5 g | IMPACT DETECTION+POSTURE MONITORING |
| ***Kangas et al. (1d)*** |  | >1.5 g<0.5g | IMPACT DETECTION+POSTURE MONITORING |
| ***Kangas et al. (2a)*** |  (start of fall) | <0.6 g>2 g<0.5g | START OF FALL+IMPACT DETECTION+POSTURE MONITORING |
| ***Kangas et al. (2b)*** |  (start of fall) | <0.6 g>1.5 g<0.5g | START OF FALL+IMPACT DETECTION+POSTURE MONITORING |
| ***Kangas et al. (3a)*** |  (start of fall) | <0.6 g>0.7 m/s>2 g<0.5g | START OF FALL+VELOCITY+IMPACT DETECTION+POSTURE MONITORING |
| ***Kangas et al. (3b)*** |  (start of fall) | <0.6 g>0.7 m/s>1.5 g<0.5g | START OF FALL+VELOCITY+IMPACT DETECTION+POSTURE MONITORING |
| ***Bourke et al. (1(a))*** |  | >UFT 1.79 g | IMPACT DETECTION |
| ***Bourke et al. (1(b))*** |  | <LFT 0.73 g | IMPACT DETECTION |
| ***Bourke et al. (2)*** |  | >1.79 g | IMPACT DETECTION+POSTURE DETECTION |
| ***Bourke et al. (3)*** |  | <-0.7 m/s>UFT 2.8 g<LFT 0.65 g60° | VELOCITY+IMPACT DETECTION+POSTURE |

(1)An angle of change can be estimated using the dot product of the acceleration vectors before a fall and after, where the vectors are from averaging over 1-second windows. (2-3)Accelerometric data were low-pass (LPF) or high-pass (HPF) filtered () with a digital second order Butterworth filter.