



Corrigendum: Unifying Speed-Accuracy Trade-Off and Cost-Benefit Trade-Off in Human Reaching Movements

Luka Peternel^{1,2}, Olivier Sigaud^{3*} and Jan Babič^{2*}

¹ HRIL Lab, Advanced Robotics, Istituto Italiano di Tecnologia, Genoa, Italy, ² Department for Automation, Biocybernetics and Robotics, Jožef Stefan Institute, Ljubljana, Slovenia, ³ Sorbonne Universités, UPMC Univ Paris 06, CNRS UMR 7222, Institut des Systèmes Intelligents et de Robotique, Paris, France

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A corrigendum on

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There were several minor typos present in the Methods section of the original article.

In the paper we defined variables **C** and **B** as torque vectors, i.e., already multiplied by \dot{q} , and therefore they should not be multiplied by \dot{q} in Equation (5). The corrected formulation of equation is:

$$\ddot{q} = M(q)^{-1}(\tau - C(q, \dot{q}) - g(q) - B(\dot{q})) \quad (5)$$

When reporting the model parameters in Table 4 in the paper, the values for inertia parameters I_1 and I_2 were accidentally switched with the values for center of mass distances s_1 and s_2 . The corrected table is:

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Mikhail Lebedev,
Duke University, United States

*Correspondence:

Olivier Sigaud
olivier.sigaud@upmc.fr
Jan Babič
jan.babic@ijs.si

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m_1	Arm mass (kg)	1.4
m_2	Forearm mass (kg)	1.1
l_1	Arm length (m)	0.3
l_2	Forearm length (m)	0.35
I_1	Arm inertia (kg.m ²)	0.025
I_2	Forearm inertia (kg.m ²)	0.045
s_1	Distance from the center of segment 1 to its center of mass (m)	0.11
s_2	Distance from the center of segment 2 to its center of mass (m)	0.16

Since we previously defined operator \times as element-wise multiplication, the joint torque calculation equation (page 12) should have a regular multiplication between matrix f_{\max} and vector \tilde{u} , and not \times operator. The corrected equation in the text is: $\tau = A^T(f_{\max}\tilde{u})$.

The authors apologize for these typos and state that they do not change the scientific conclusions in any way.

The original article has been updated.

Conflict of Interest Statement: The authors declare that the research was conducted in the absence of any commercial or financial relationships that could be construed as a potential conflict of interest.

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