



## OPEN ACCESS

EDITED AND REVIEWED BY  
Dongming Gan,  
Purdue University, United States

\*CORRESPONDENCE  
Hongliu Yu  
✉ yhl98@hotmail.com

RECEIVED 30 July 2023  
ACCEPTED 01 August 2023  
PUBLISHED 08 August 2023

CITATION  
Xie Q, Meng Q, Yu W, Wu Z, Xu R, Zeng Q,  
Zhou Z, Yang T and Yu H (2023) Corrigendum:  
Design of a SMA-based soft composite  
structure for wearable rehabilitation gloves.  
*Front. Neurobot.* 17:1269432.  
doi: 10.3389/fnbot.2023.1269432

COPYRIGHT  
© 2023 Xie, Meng, Yu, Wu, Xu, Zeng, Zhou,  
Yang and Yu. This is an open-access article  
distributed under the terms of the [Creative Commons Attribution License \(CC BY\)](https://creativecommons.org/licenses/by/4.0/). The use,  
distribution or reproduction in other forums is  
permitted, provided the original author(s) and  
the copyright owner(s) are credited and that  
the original publication in this journal is cited, in  
accordance with accepted academic practice.  
No use, distribution or reproduction is  
permitted which does not comply with these  
terms.

# Corrigendum: Design of a SMA-based soft composite structure for wearable rehabilitation gloves

Qiaolian Xie<sup>1,2,3</sup>, Qiaoling Meng<sup>1,2</sup>, Wenwei Yu<sup>3,4</sup>, Zhiyu Wu<sup>1,2</sup>,  
Rongna Xu<sup>1,2</sup>, Qingxin Zeng<sup>1,2</sup>, Zhongchao Zhou<sup>3</sup>, Tianyi Yang<sup>3</sup>  
and Hongliu Yu<sup>1,2\*</sup>

<sup>1</sup>Institute of Rehabilitation Engineering and Technology, University of Shanghai for Science and Technology, Shanghai, China, <sup>2</sup>Shanghai Engineering Research Center of Assistive Devices, Shanghai, China, <sup>3</sup>Department of Medical Engineering, Chiba University, Chiba, Japan, <sup>4</sup>Center for Frontier Medical Engineering, Chiba University, Chiba, Japan

## KEYWORDS

soft exoskeleton, shape memory alloys (SMA), soft composite structure, hand exoskeleton, SMA actuator

A corrigendum on  
[Design of a SMA-based soft composite structure for wearable rehabilitation gloves](#)

by Xie, Q., Meng, Q., Yu, W., Wu, Z., Xu, R., Zeng, Q., Zhou, Z., Yang, T., and Yu, H. (2023). *Front. Neurobot.* 17:1047493. doi: 10.3389/fnbot.2023.1047493

In the published article, there was an error. The finger angles were described as flexed, whereas they should have been depicted as extended.

A correction has been made to 3. Experimental results, 3.4. *Experiment of fingers motion angles*, paragraph one. These sentences previously stated:

“The angles of five fingers extension were recorded, as shown in Figure 11B. The motion range of thumb extension is about 100° and its cycle is about 13 s. The motion range of forefinger extension is about 105° and its cycle is about 17 s. The motion range of middle finger extension is about 90° and its cycle is about 15 s. The motion range of extension of the ring and little fingers is about 110° and its cycle is about 19 s.”

The corrected sentences appears below:

“The angles of five fingers extension were recorded, as shown in Figure 11B. The motion range of thumb extension is about 40° and its cycle is about 12 s. The motion range of forefinger extension is about 30° and its cycle is about 13 s. The motion range of middle finger extension is about 40° and its cycle is about 12 s. The motion range of extension of the ring and little fingers is about 40° and its cycle is about 12 s.”

The authors apologize for this error and state that this does not change the scientific conclusions of the article in any way. The original article has been updated.

## Publisher's note

All claims expressed in this article are solely those of the authors and do not necessarily represent those of their affiliated organizations, or those of the publisher, the editors and the reviewers. Any product that may be evaluated in this article, or claim that may be made by its manufacturer, is not guaranteed or endorsed by the publisher.