

# The International Journal of Robotics Research

<http://ijr.sagepub.com/>

---

## Corrigendum

SAGE Publications

*The International Journal of Robotics Research* published online 18 February 2011

DOI: 10.1177/0278364911400536

The online version of this article can be found at:

<http://ijr.sagepub.com/content/early/2011/02/07/0278364911400536>

---

Published by:



<http://www.sagepublications.com>

On behalf of:



Multimedia Archives

**Additional services and information for *The International Journal of Robotics Research* can be found at:**

**Email Alerts:** <http://ijr.sagepub.com/cgi/alerts>

**Subscriptions:** <http://ijr.sagepub.com/subscriptions>

**Reprints:** <http://www.sagepub.com/journalsReprints.nav>

**Permissions:** <http://www.sagepub.com/journalsPermissions.nav>



---

## Corrigendum

The International Journal of  
Robotics Research  
00(000) 1  
© The Author(s) 2011  
Reprints and permission:  
[sagepub.co.uk/journalsPermissions.nav](http://sagepub.co.uk/journalsPermissions.nav)  
DOI: 10.1177/0278364911400536  
[ijr.sagepub.com](http://ijr.sagepub.com)



Corrigendum to Design of an active one-degree-of-freedom lower-limb exoskeleton with inertia compensation by Gabriel Aguirre-Ollinger, J. Edward Colgate, Michael A. Peshkin and Ambarish Goswami, *International Journal of Robotics Research* 2010; published online first December 7, 2010 [DOI: 10.1177/0278364910385730].

The affiliation for Dr Ambarish Goswami, fourth author of this paper, was published incorrectly. His correct affiliation is Honda Research Institute, Mountain View, CA, USA.