

## List of Corrigenda

Makita, Satoshi, Nakamura, Shinobu, Maeda, Yusuke:

### “Joint Torque Optimization for Grasp/Graspless Manipulation”

Proc. of the 3rd Int. Sym. on Measurement, Analysis and Modeling for Human Functions,  
pp. 203–210, 2007.

I really apologize and correct my paper.

- p. 205, Eq. (4)

$$\text{(Incorrect)} \quad \begin{bmatrix} W & J^T \end{bmatrix} \mathbf{f} = \begin{bmatrix} -\omega_{\text{ext}} \\ \boldsymbol{\tau} \end{bmatrix} \Rightarrow \mathbf{A} \mathbf{f} = \boldsymbol{\omega}$$

$$\text{(Correct)} \quad \begin{bmatrix} W \\ J^T \end{bmatrix} \mathbf{f} = \begin{bmatrix} -\omega_{\text{ext}} \\ \boldsymbol{\tau} \end{bmatrix} \Rightarrow \mathbf{A}^T \mathbf{f} = \boldsymbol{\omega}$$

- p. 206, Eq. (10)

$$\text{(Incorrect)} \quad \dot{\mathbf{Y}} = \mathbf{S}\mathbf{q}, \quad \mathbf{q} \geq \mathbf{0}$$

$$\text{(Correct)} \quad \dot{\mathbf{Y}} = \mathbf{S}\mathbf{q}, \quad \mathbf{q} > \mathbf{0}$$

- p. 207, Eq. (11)

$$\text{(Incorrect)} \quad \mathbf{B}\mathbf{A} \begin{bmatrix} \mathbf{V} \\ -\dot{\boldsymbol{\theta}} \end{bmatrix} = \mathbf{T}\mathbf{S}\mathbf{q}, \quad \mathbf{q} \geq \mathbf{0}$$

$$\text{(Correct)} \quad \mathbf{B}\mathbf{A} \begin{bmatrix} \mathbf{V} \\ -\dot{\boldsymbol{\theta}} \end{bmatrix} = \mathbf{T}\mathbf{S}\mathbf{q}, \quad \mathbf{q} > \mathbf{0}$$

- p. 208, Eq. (15)

$$\text{(Incorrect)} \quad \dots \mathbf{A} \mathbf{f} = \boldsymbol{\omega}, \dots$$

$$\text{(Correct)} \quad \dots \mathbf{A}^T \mathbf{f} = \boldsymbol{\omega}, \dots$$

- p. 208, Eq. (16)

$$\text{(Incorrect)} \quad \dots \mathbf{A} \mathbf{f} = \boldsymbol{\omega}, \dots$$

$$\text{(Correct)} \quad \dots \mathbf{A}^T \mathbf{f} = \boldsymbol{\omega}, \dots$$