Errata

Correction to “The VSPA Foot: A Quasi-Passive Ankle-Foot Prosthesis With Continuously Variable Stiffness”

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In the above paper [1], Eq. (7) should have appeared as follows:

\[
\alpha (\theta) = \sin^{-1} \left( \frac{L}{r} \sin (\sigma + y (\theta)) \right) - \omega
\]

REFERENCES