Corrigendum: Inverse Kinematics at the Anthropomorphic Robots, by a Trigonometric Method

¹Relly Victoria V. Petrescu, ²Raffaella Aversa, ³Bilal Akash, ⁴Ronald B. Bucinell, ²Antonio Apicella and ¹Florian Ion T. Petrescu

¹ARoTMM-IFToMM, Bucharest Polytechnic University, Bucharest, (CE) Romania
²Advanced Material Lab, Department of Architecture and Industrial Design,
Second University of Naples, 81031 Aversa (CE) Italy
³Dean of School of Graduate Studies and Research, American University of Ras Al Khaimah, UAE
⁴Union College, USA

Correction to: American Journal of Engineering and Applied Sciences http://doi.org/10.3844/ajeassp.2017.394.411, published online 27 April 2017; updated 29 August 2019

The original version of this Article contained Mr. MirMilad Mirsayar as a Co-Author. Mr. Mirsayar has not contributed to the preparation and publication of this manuscript.

These errors have now been corrected in the HTML and PDF versions of the Article. http://doi.org/10.3844/ajeassp.2017.394.411.



© 2018 The Author(s). This open access article is distributed under a Creative Commons Attribution (CC-BY) 3.0 license.