

Erratum

Erratum: Jamšek et al. Gaussian Mixture Models for Control of Quasi-Passive Spinal Exoskeletons. *Sensors* 2020, 20, 2705Marko Jamšek ^{1,2,*} , Tadej Petrič ¹  and Jan Babič ¹ 

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There was an error in the original article [1]. The variable used for the superscript in the denominator of the equation, denoting the dimensionality of the model, was incorrectly written as K and thus conflicted with the variable denoting the number of Gaussian mixtures. A correction has therefore been made to Section 2.3, Equation (4):

$$p_j(x) = \sum_{k=1}^K \tau_k \left(\frac{e^{-\frac{1}{2}(x-\mu_k)^T \Sigma_k^{-1}(x-\mu_k)}}{\sqrt{(2\pi)^D |\Sigma_k|}} \right) \quad (4)$$

where D is the dimensionality of the model (6 in our case).



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Reference

1. Jamšek, M.; Petrič, T.; Babič, J. Gaussian Mixture Models for Control of Quasi-Passive Spinal Exoskeletons. *Sensors* **2020**, 20, 2705. [[CrossRef](#)] [[PubMed](#)]