
Correction

Correction: Greve, D.; Kreischer, C. Methodology for Integrated Design Optimization of Actuation Systems for Exoskeletons. *Robotics* 2024, 13, 158

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Text Correction

There was an error in the original publication [1]. Exponent 2 is missing in Equation (8). A correction has been made to Equation (8):

$$i_{\text{RMS},j} = \sqrt{\frac{1}{(t_1 - t_0)} \int_{t_0}^{t_1} \left(\frac{i_{q,j}(t)}{\sqrt{2}} \right)^2 dt} \leq i_{\text{RMS,nom},j} \quad (8)$$

The authors state that the scientific conclusions are unaffected. This correction was approved by the Academic Editor. The original publication has also been updated.

Reference

1. Greve, D.; Kreischer, C. Methodology for Integrated Design Optimization of Actuation Systems for Exoskeletons. *Robotics* **2024**, *13*, 158. [[CrossRef](#)]

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