Correction to: A Geometric Algebra Based Higher Dimensional Approximation Method for Statics and Kinematics of Robotic Manipulators

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Section 3.1.1. Typographic error in Eq. (41c): the subscript ‘3’ in ‘ δ_3 ’ (coloured in red) should be a ‘4’ to give ‘ δ_4 ’

Section 3.2.2. Typographic error in Eqs. (45c–45h): there is a double wedge ‘ $\wedge \wedge$ ’ symbol in the centre of each equation which should be replaced with a single wedge ‘ $\wedge$ ’ symbol.

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