



# Correction to: Bio-Inspired Modular Relative Jacobian for Holistically Controlled Four-Arm Manipulators Using Opposite and Adjacent Dual-Arm Pairs

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## Correction to:

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In the original publication, Figs. 6 and 7 are published incorrectly. The correct figures are given below. The original publication has been updated of the same.

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The original article can be found online at <https://doi.org/10.1007/s13369-021-06046-z>.

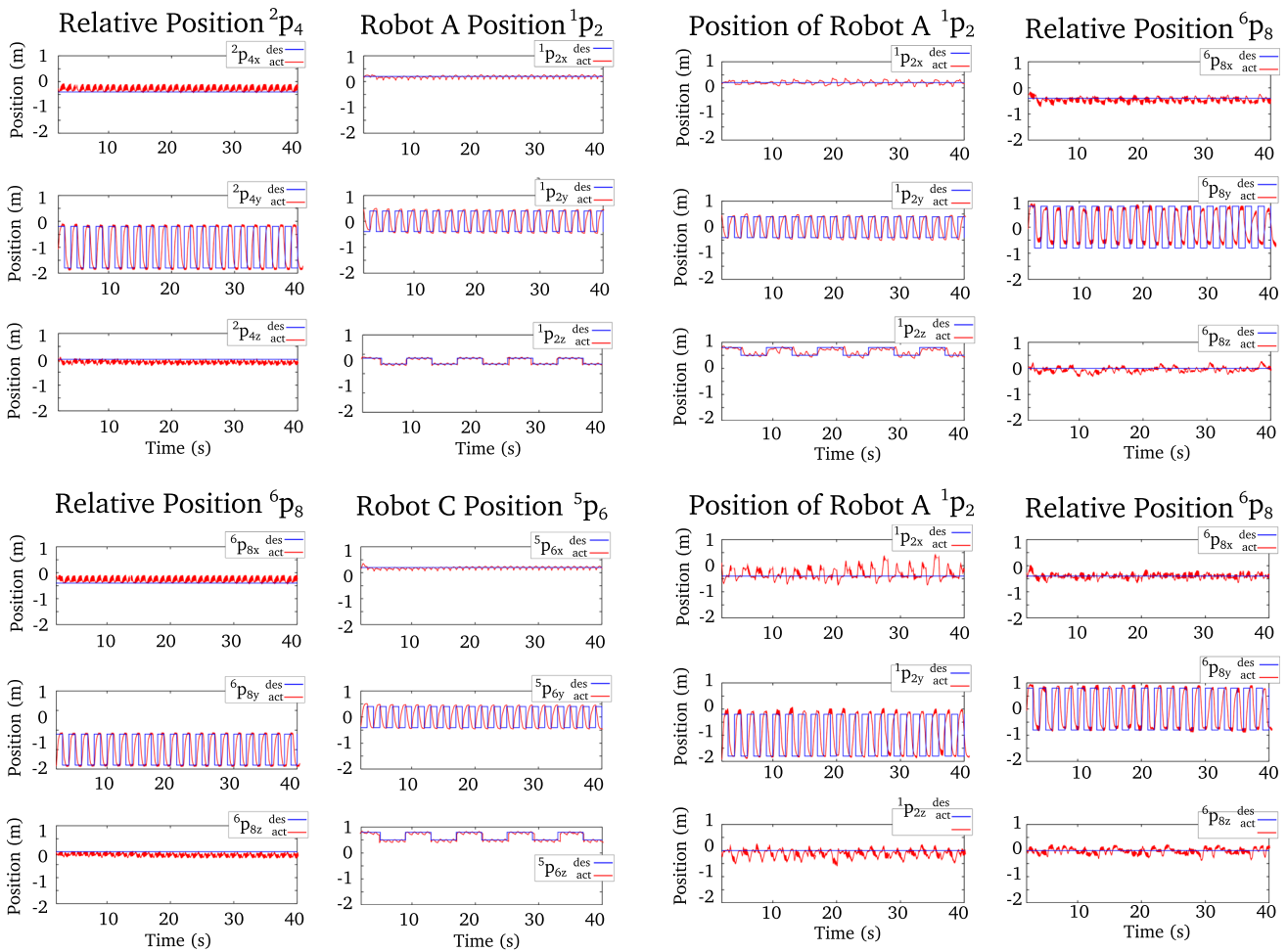
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**Fig. 6** Case 1 Pacing walking cycle results. The graphs show desired and actual values of the relative position of the front legs,  ${}^2\mathbf{p}_4$ , and the hind legs,  ${}^6\mathbf{p}_8$ , as well as the absolute position of Robot A,  ${}^1\mathbf{p}_2$ , and Robot C,  ${}^5\mathbf{p}_6$ . The front legs movement,  ${}^2\mathbf{p}_4$ , is the main task, while  ${}^1\mathbf{p}_2$ ,  ${}^6\mathbf{p}_8$ , and  ${}^5\mathbf{p}_6$  are the secondary tasks in decreasing hierarchy

**Fig. 7** Case 4 Counter-lateral leg pairing with equal null-space tasks hierarchy. The graphs show desired and actual values of counter-lateral leg pairing of Robot A and Robot C with the corresponding movement  ${}^2\mathbf{p}_6$  as the main task. The other legs movement now lies in the null space with equal hierarchy of task execution: front legs pair  ${}^2\mathbf{p}_4$ , Robot A  ${}^1\mathbf{p}_2$ , and hind legs pair  ${}^6\mathbf{p}_8$