

Correction to: The first distributed-mass high-performance programmable optoelectromechanical steerable motion-wave sensors focused on sophisticated biomedical applications

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In this article the delimiters “<” and “>” to indicate the range of values were omitted from Eqs. (11), (12), and (19) during production of the published article.

The **incorrect** equations were as follows:

$$d_n = d_{pn} \cos \theta_H \cos \theta_V$$

$$d_{pn} = d_p / d_{p,\min}, d_p = d_{p,\min}, d_{p,\max}, d_{pn} = 1, d_{p,\max} / d_{p,\min} \quad (11)$$

$$d = [d_A \cos \theta_H + d_B \cos (\theta_H - \theta_{AB})] \cdot \cos \theta_V$$

$$d_A \& d_B = d_{p,\min}, d_{p,\max} \quad (12)$$

$$d = d_A \cos \theta_H + d_B \cos (\theta_H - 120^\circ) + d_C \cos (\theta_H + 120^\circ)$$

$$= d_i \cos \theta_H + d_q \sin \theta_H = d_s \cos (\theta_H - \theta_s)$$

$$d_A \& d_B \& d_C = d_{p,\min}, d_{p,\max}, d_i = d_A - \frac{d_B + d_C}{2},$$

$$d_q = \frac{\sqrt{3}}{2} (d_B - d_C), d_s = \sqrt{d_i^2 + d_q^2}, \theta_s = \tan^{-1} \left(\frac{d_q}{d_i} \right) \quad (19)$$

The **correct** equations are as follows:

$$d_n = d_{pn} \cos \theta_H \cos \theta_V$$

$$d_{pn} = d_p / d_{p,\min}, d_p = \langle d_{p,\min}, d_{p,\max} \rangle, d_{pn} = \langle 1, d_{p,\max} / d_{p,\min} \rangle \quad (11)$$

$$d = [d_A \cos \theta_H + d_B \cos (\theta_H - \theta_{AB})] \cdot \cos \theta_V$$

$$d_A \& d_B = \langle d_{p,\min}, d_{p,\max} \rangle \quad (12)$$

$$d = d_A \cos \theta_H + d_B \cos (\theta_H - 120^\circ) + d_C \cos (\theta_H + 120^\circ)$$

$$= d_i \cos \theta_H + d_q \sin \theta_H = d_s \cos (\theta_H - \theta_s)$$

$$d_A \& d_B \& d_C = \langle d_{p,\min}, d_{p,\max} \rangle, d_i = d_A - \frac{d_B + d_C}{2},$$

$$d_q = \frac{\sqrt{3}}{2} (d_B - d_C), d_s = \sqrt{d_i^2 + d_q^2}, \theta_s = \tan^{-1} \left(\frac{d_q}{d_i} \right) \quad (19)$$

The original article has been corrected.

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