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ERRATUM

A dynamics formulation of general constrained robots

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With reference to section **3.3 Coordinated multiple manipulators**

1) The correct text for the beginning (the first two lines) of the explanation for Step 4 should begin as follows:

In Step 4, $\dot{q}_a = [\dot{q}_1^T, \dot{q}_2^T, \cdots, \dot{q}_h^T]^T \in \Re^{6h}$ with $\dot{q}_i = [\dot{q}_{i1}, \dot{q}_{i2}, \cdots, \dot{q}_{i6}]^T \in \Re^6$, $i = 1, 2, \cdots, h$, and $\dot{q}_u = 0$ are specified. Matrix $\mathcal{T}_a$ is formed as

2) The correct text for the beginning (the first two lines) of the explanation for Step 8 should begin as follows:

In Step 8, $n = 6h$ is obtained from (13). Furthermore, it yields

$$\dot{q} = \dot{q}_a \in \Re^{6h}$$

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