



Corrigendum: Sliding Mode Tracking Control of a Wire-Driven Upper-Limb Rehabilitation Robot with Nonlinear Disturbance Observer

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In the original article, there was an error. The article partly overlaps with previously published conference proceedings. A correction has been made to add an Acknowledgments section.

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This article is partially based on our previous work which is shown in a conference paper (1).

The authors apologize for this error and state that this does not change the scientific conclusions of the article in any way.

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1. Niu J, Yang Q, Chen G, Song R. Nonlinear disturbance observer based sliding mode control of a cable-driven rehabilitation robot. *IEEE Int Conf Rehabil Robot.* (2017) 2017:664–9. doi: 10.1109/icorr.2017.8009324

Conflict of Interest Statement: The authors declare that the research was conducted in the absence of any commercial or financial relationships that could be construed as a potential conflict of interest.

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