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To Whom It May Concern

In order to properly acknowledge the source, after a request from the authors of the paper, the following paragraphs of the paper have been corrected with quotation marks and references:

The Wiimote was used to measure flexion, adduction in 90° flexion and internal rotation in 90° flexion in 20 healthy volunteers. "*The motion capture system employed for the purpose of this research comprised an off-the-shelf gaming sensor, i.e. the Ninteno Wiimote, and a bespoke communication interface between the Wiimotes (up to two) and local computers connected by Bluetooth and remote via the Internet*" (Tsekleves, et al., 2014).

"*The motion data received by the terminals undergo a process of smoothing and multiplexing by using a data fusion algorithm to achieve higher accuracy and precision. The end results are then mapped into quaternion forms that translate the orientation of a constructed 3D body model and are free from gimbal-lock. The angular rate measurements captured by the gyroscope sensor can be used to distinguish true linear motion from the accelerometer readings. The gyroscope is not free from noise, but since the measured rotation is less sensitive to linear mechanical movements and without amplifying hand jitter, both of which are experienced with accelerometers, it allows for the capture of more complex orientation with a relatively better estimate than we would obtain by using accelerometers alone. A sensible approach for maximising efficiency is to average or concatenate the data that come from the accelerometer and gyroscope by using a data fusion algorithm. Simultaneously, we were able to employ a smoothing algorithm to remove any excessive noise from the signals while still retaining the useful information. Filtering out and removing as much random noise as possible from the sensors' outputed raw information whilst retaining quality data is of fundamental importance*" (Tsekleves, et al., 2012), (Warland , et al., 2012), (Tsekleves , et al., 2014).

"*The Wiimote sensors are very responsive but cannot respond to the linear movement which accelerometers specialise in capturing. However, as described in the above section, when a gyroscope and an accelerometer are combined, the pairing of sensors facilitates a highly accurate one-to-one representation of the control device in the 3D space" (Tsekleves, et al., 2012). The quaternion data are forwarded locally or online and thus manipulate a virtual 3D object on the local computer or provide biofeedback to the clinician (remote terminal). The aforementioned feature enables the remote monitoring of the whole procedure* (Tsekleves, et al., 2012), (Ojeda & Borenstein, 2002).

Sincerely,

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