CORRECTION

Correction to: A hydrodynamic model of bridle towed system

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Correction to: Journal of Marine Science and Technology
https://doi.org/10.1007/s00773-018-0546-2

In the original publication of the article Eqs. (1) and (10) are incorrectly published. The correct equations are provided in this correction article.

$$
\begin{cases}
m_k(\dot{u}_k + q_k w_k - v_k r_k) = X_{Hk} \\
\quad + X_{Pk} + X_{Rk} + X_{Tk} \\
m_k(\dot{v}_k + u_k r_k - p_k w_k) = Y_{Hk} \\
\quad + Y_{Pk} + Y_{Rk} + Y_{Tk} \\
m_k(\dot{w}_k + p_k v_k - q_k u_k) = Z_{Hk} \\
\quad + Z_{Pk} + Z_{Rk} + Z_{Tk} \\
I_{xk}\dot{p}_k + (I_{zk} - I_{yk})q_k r_k = K_{Hk} \\
\quad + K_{Pk} + K_{Rk} + K_{Tk} \\
I_{yk}\dot{q}_k + (I_{xk} - I_{zk})p_k r_k = M_{Hk} \\
\quad + M_{Pk} + M_{Rk} + M_{Tk} \\
I_{zk}\dot{r}_k + (I_{yk} - I_{xk})p_k q_k = N_{Hk} \\
\quad + N_{Pk} + N_{Rk} + N_{Tk}
\end{cases}
\tag{1}
$$

$$
\begin{bmatrix}
\mathrm{d}X/\mathrm{d}s \\
\mathrm{d}Y/\mathrm{d}s \\
\mathrm{d}Z/\mathrm{d}s
\end{bmatrix}
= (1 + \varepsilon)T_C^{-1}
\begin{bmatrix}
0 \\
1 \\
0
\end{bmatrix},
\tag{10}
$$

In addition, the third sentence in the first paragraph of Sect. 2.1, "the added masses and inertia are represented by m and J with subscripts of x, y and z" should be cancelled.

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