Publisher Correction to: 3D-model for Active Vibration Control of Rotating Machines Mounted on Active Machine Foot Mounts Using Vibration Mode Coupling by Asymmetry

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The publication of this article unfortunately contained mistakes due to publisher's error. Please see the corrected parts below:

$$\begin{aligned} \mathbf{A}_{st} &= \begin{bmatrix} \mathbf{0}_6 & \mathbf{I}_6 \\ -\mathbf{M}^{-1} \cdot \mathbf{C} & -\mathbf{M}^{-1} \cdot (\mathbf{D} + \mathbf{G}) \end{bmatrix}; \quad \mathbf{B}_{st} = \begin{bmatrix} \mathbf{0}_6 \\ \mathbf{M}^{-1} \end{bmatrix} \\ \mathbf{C}_{st} &= \begin{bmatrix} \mathbf{I}_6 & \mathbf{0}_6 \\ \mathbf{0}_6 & \mathbf{I}_6 \\ -\mathbf{M}^{-1} \cdot \mathbf{C} & -\mathbf{M}^{-1} \cdot (\mathbf{D} + \mathbf{G}) \end{bmatrix}; \quad \mathbf{D}_{st} = \begin{bmatrix} \mathbf{0}_6 \\ \mathbf{0}_6 \\ \mathbf{M}^{-1} \end{bmatrix} \end{aligned} \quad (21)$$

to set to the zero vector $\mathbf{E}(s) = \mathbf{0}$. Finally, the poles can be

$$\begin{aligned} \mathbf{G}_{\gamma, \kappa}(j\omega) &= \frac{\mathbf{Y}_{\gamma, \kappa}(j\omega)}{E_{\kappa}(j\omega)} = \mathbf{G}_{\gamma}(j\omega) \cdot \mathbf{P}_{e, \kappa} \\ &= \left[\mathbf{I}_{18} + \left(\mathbf{C}_{st} \cdot (\mathbf{I}_{12} \cdot j\omega - \mathbf{A}_{st})^{-1} \cdot \mathbf{B}_{st} + \mathbf{D}_{st} \right) \cdot \mathbf{T}_{st, \gamma}(j\omega) \right]^{-1} \\ &\quad \cdot \left[\mathbf{C}_{st} \cdot (\mathbf{I}_{12} \cdot j\omega - \mathbf{A}_{st})^{-1} \cdot \mathbf{B}_{st} + \mathbf{D}_{st} \right] \cdot \mathbf{P}_{e, \kappa} \end{aligned} \quad (41)$$

$$\tilde{\mathbf{M}} \cdot \ddot{\mathbf{q}} + (\tilde{\mathbf{D}} + \mathbf{G}) \cdot \dot{\mathbf{q}} + \tilde{\mathbf{C}} \cdot \mathbf{q} = \mathbf{0} \quad (53)$$

$$[\tilde{\mathbf{M}} \cdot \lambda^2 + (\tilde{\mathbf{D}} + \mathbf{G}) \cdot \lambda + \tilde{\mathbf{C}}] \cdot \hat{\mathbf{q}} = \mathbf{0} \quad (55)$$

sources of excitation and the blocks $v_{zb}D$, $v_{zb}N$, $v_{yb}D$.

with $\mathbf{T}_z(s)$, $\mathbf{T}_v(s)$, $\mathbf{T}_a(s) \in \mathbb{C}^{6 \times 6}$ and $\mathbf{T}_0(s) = \mathbf{0}_6 \in \mathbb{R}^{6 \times 6}$ set to the zero vector $\mathbf{E}(s) = \mathbf{0}$.

$$\left[\mathbf{I}_{12} \cdot s - \mathbf{A}_{st} + \mathbf{B}_{st} \cdot \mathbf{T}_{st, \gamma} \cdot [\mathbf{I}_{18} + \mathbf{D}_{st} \cdot \mathbf{T}_{st, \gamma}]^{-1} \cdot \mathbf{C}_{st} \right] \cdot \mathbf{X}(s) = \mathbf{0} \quad (136)$$

The original article has been corrected.

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