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Collision Avoidance by a Ship with a Moving Obstacle: Computation of Feasible Command Strategies

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Abstract. Typographical errors on page 57 of Ref. 1 are corrected.

Key Words. Collision avoidance, ship maneuvering, feasible command strategies.

On page 57, Lines 11, 12 should read

$$x_1 = U, \quad x_2 = \beta, \quad x_3 = r, \quad x_{s3} = r',$$

$$x_4 = \theta, \quad x_5 = X_I, \quad x_6 = Y_I.$$

Equations (12) and (13) should read

$$dx_1/dt = (x_1^2/(m_1 m_2 L))$$

$$\times [-x_{s3} \cos x_2 \sin x_2 (m_2^2 - m_1^2) + X' m_2 \cos x_2 - Y' m_1 \sin x_2], \qquad (12)$$

$$dx_2/dt = (x_1/(m_1 m_2 L))$$

$$\times [x_{s3} (m_2^2 \sin^2 x_2 + m_1^2 \cos^2 x_2) - m_2 X' \sin x_2 - m_1 Y' \cos x_2]. \qquad (13)$$

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Reference

1. YAVIN, Y., FRANGOS, C., MILOH, T., and ZILMAN, G., *Collision Avoidance by a Ship with a Moving Obstacle: Computation of Feasible Command Strategies*, Journal of Optimization Theory and Applications, Vol. 93, No. 1, pp. 53–66, 1997.