

Proofs of SIMPAT_423 corrections

Response to query:

AMESim is the software name and not an author name.

Authors' address, line 6: name of the institute

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Equations (25), (26) and (27): space and minus sign must be more clearly displayed in front of the equations

$$\begin{array}{l}
 \text{geometrical} \quad \left\{ \begin{array}{l} -(x_N^0 - x_M^0) \sin \theta_N^0 + (y_N^0 - y_M^0) \cos \theta_N^0 = 0 \end{array} \right. \\
 \text{kinematical} \quad \left\{ \begin{array}{l} -(v_{x_N}^0 - v_{x_M}^0) \sin \theta_N^0 + (v_{y_N}^0 - v_{y_M}^0) \cos \theta_N^0 \\ -\omega_N^0 [(x_N^0 - x_M^0) \cos \theta_N^0 + (y_N^0 - y_M^0) \sin \theta_N^0] = 0 \end{array} \right. \\
 \text{acceleration} \quad \left\{ \begin{array}{l} -(a_{x_N}^0 - a_{x_M}^0) \sin \theta_N^0 + (a_{y_N}^0 - a_{y_M}^0) \cos \theta_N^0 \\ -\gamma_N^0 [(x_N^0 - x_M^0) \cos \theta_N^0 + (y_N^0 - y_M^0) \sin \theta_N^0] \\ -2\omega_N^0 [(v_{x_N}^0 - v_{x_M}^0) \cos \theta_N^0 + (v_{y_N}^0 - v_{y_M}^0) \sin \theta_N^0] = 0 \end{array} \right.
 \end{array}$$

Equation (38): terms are missing between the sixth and seventh lines of the equation

$$\begin{array}{l}
 \dots \\
 - (f_{k,\vec{x}_{il},\vec{y}_{jl}} - f_{k,\vec{y}_{il},\vec{x}_{jl}}) \sin (\theta_M^0 - \theta_N^0) \\
 - 2v_{x_M}^0 \left[\omega_M^0 \left(f_{k,\vec{OM},\vec{x}_{il}} \sin \theta_M^0 + f_{k,\vec{OM},\vec{y}_{il}} \cos \theta_M^0 \right) \right. \\
 \left. + \omega_N^0 \left(f_{k,\vec{OM},\vec{x}_{jl}} \sin \theta_N^0 + f_{k,\vec{OM},\vec{y}_{jl}} \cos \theta_N^0 \right) \right] \\
 + 2v_{y_M}^0 \left[\omega_M^0 \left(f_{k,\vec{OM},\vec{x}_{il}} \cos \theta_M^0 - f_{k,\vec{OM},\vec{y}_{il}} \sin \theta_M^0 \right) \right. \\
 \dots
 \end{array}$$

References [6]: in the proceedings title, 'Mechanical' instead of 'Mechancial'.