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FRANC FORSTNERIČ

The condition on stabilisers in Theorem 1.1 does not suffice for the conclusion. Here is the correct statement supported by the proof.

Theorem 0.1. *Let G be a finite group acting effectively on a connected open Riemann surface X by holomorphic automorphisms, and acting on the Euclidean space $\mathbb{R}^n$, $n \geq 3$, by orthogonal transformations. If for every point $x \in X$ with nontrivial stabiliser G_x there exists a G_x-equivariant conformal linear embedding $T_xX \to \mathbb{R}^n$, then there exists a G-equivariant conformal minimal immersion $F : X \to \mathbb{R}^n$.*

The condition on the stabilisers can equivalently be stated as follows:

If g is a generator of G_x whose differential dg_x acts on the tangent space T_xX as a rotation for the angle ϕ, then there is a two-dimensional linear subspace $\Lambda_x \subset \mathbb{R}^n$ on which g also acts as a rotation for the angle ϕ.

This condition is also necessary as shown by Remark 1.2 and Proposition 2.2 (b) in the original paper. A similar correction must be made in Theorems 5.3 and 6.3. The remaining results of the paper are not affected.

Nevertheless, under the original assumption in Theorem 1.1 there exists a G-equivariant conformal minimal surface $F : X \to \mathrm{R}^n$ which is branched precisely at those points $x \in X$ with nontrivial stabiliser G_x at which the condition in Theorem 0.1 fails. See [1, Remark 1.2 and Theorem 2.5].

AI Declaration: No AI tools were used in the preparation of this work.

References

[1] A. Alarcón and F. Forstnerič, The Calabi–Yau and Sullivan conjectures for minimal surfaces with symmetries. `https://arxiv.org/abs/2610.31847`.

Franc Forstnerič, Faculty of Mathematics and Physics, University of Ljubljana, Jadranska 19, 1000 Ljubljana, Slovenia

Franc Forstnerič, Institute of Mathematics, Physics, and Mechanics, Jadranska 19, 1000 Ljubljana, Slovenia

Email address: `franc.forstneric@fmf.uni-lj.si`

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