Corrigendum

Corrigendum to “Mobile Robot Simultaneous Localization and Mapping Based on a Monocular Camera”

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In the article titled “Mobile Robot Simultaneous Localization and Mapping Based on a Monocular Camera” [1], there were errors in (7), (8), (9), (14), (16), (18), and (19), which should be corrected as follows:

$$\arg \min_{\mathbf{x}} \sum \|r_p(\mathbf{x})\|^2, \quad (7)$$

$$\arg \min_{\mathbf{x}, d} \sum L(d(u) - d_g(u)) \|r_p(\mathbf{x})\|^2 + \|r_d(u, d)\|^2, \quad (8)$$

$$L(x) = \begin{cases} 1, & |x| \leq \sigma, \\ 0, & \text{others,} \end{cases} \quad (8)$$

$$\arg \min_{\mathbf{x}} \sum L(d - d_g) \|r_p(\mathbf{x})\|^2, \quad (9)$$

$$\arg \min_d \sum \|r_d(u, d)\|^2, \quad (14)$$

$$\min_{\mathbf{x}} \sum w(r_p) \|r_p(\mathbf{x})\|^2, \quad (16)$$

$$\xi = \arg \min_{\xi} \sum_i w(e_i) \|e_i\|^2, \quad (18)$$

$$s(u_j^i) = \begin{cases} \|r_j\| \leq \sigma_i, & \text{accept,} \\ \|r_j\| > \sigma_i, & \text{reject,} \end{cases} \quad (19)$$

$$r_j = \pi(H_i v_j^i) - u_j^i.$$

References

- [1] S. Jia, K. Wang, and X. Li, “Mobile robot simultaneous localization and mapping based on a monocular camera,” *Journal of Robotics*, vol. 2016, Article ID 7630340, 11 pages, 2016.