

## Corrigendum

# Corrigendum to “A Novel Improved Probability-Guided RANSAC Algorithm for Robot 3D Map Building”

Songmin Jia,<sup>1,2,3</sup> Ke Wang,<sup>1,2,3</sup> Xiuzhi Li,<sup>1,2,3</sup> and Tao Xu<sup>1,2,3,4</sup>

<sup>1</sup>College of Electronic and Control Engineering, Beijing University of Technology, Beijing 100124, China

<sup>2</sup>Beijing Key Laboratory of Computational Intelligence and Intelligent System, Beijing 100124, China

<sup>3</sup>Engineering Research Center of Digital Community, Ministry of Education, Beijing 100124, China

<sup>4</sup>School of Mechanical and Electrical Engineering, Henan Institute of Science and Technology, Xinxiang 453003, China

Correspondence should be addressed to Ke Wang; kwangs@sina.com

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In the article titled “A Novel Improved Probability-Guided RANSAC Algorithm for Robot 3D Map Building” [1], there were errors in equations (21), (29), (31), and (32), which should be corrected as follows:

$$E = \arg \min_{T_k} \frac{1}{N} \sum_{\Omega} \|r_i(\xi)\|^2 \quad (21)$$

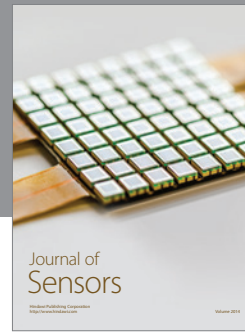
$$E = \sum_{i=0}^n \|r_i\|^2, \quad r_i = \pi(Hu_i^{\text{ref}}) - u_i \quad (29)$$

$$m'Fm^T = 0 \quad (31)$$

$$r = \frac{(m'Fm^T)^2}{\|F^T m'^T\|^2 + \|Fm^T\|^2} \quad (32)$$

## References

- [1] S. Jia, K. Wang, X. Li, and T. Xu, “A novel improved probability-guided RANSAC algorithm for robot 3D map building,” *Journal of Sensors*, vol. 2016, Article ID 3243842, 18 pages, 2016.



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