

Erratum

Erratum to “LiDAR-Camera Calibration Under Arbitrary Configurations: Observability and Methods”

Bo Fu, Yue Wang , *Member, IEEE*, Xiaqing Ding, Yanmei Jiao, Li Tang, and Rong Xiong , *Member, IEEE*

In the above article [1], there is a presentation error in the derived conclusion of the theory in Section III-B2-a “Observation of one plane” on page 3094. The error presentation in this article is as follows:

The result is explained as when observing only one chess-board, any translation parallel to the plane’s normal and any rotation around the plane’s normal are unobservable.

The corrected presentation should be:

The result is explained as when observing only one chess-board, any translation perpendicular to the plane’s normal and any rotation around the plane’s normal are unobservable.

The same conclusion is also presented in Appendix A1 on page 3100 such that the same presentation error should be corrected as mentioned earlier.

REFERENCES

- [1] B. Fu, Y. Wang, X. Ding, Y. Jiao, L. Tang, and R. Xiong, “LiDAR-camera calibration under arbitrary configurations: Observability and methods,” *IEEE Trans. Instrum. Meas.*, vol. 69, no. 6, pp. 3089–3102, Jun. 2020.

Manuscript received October 28, 2020; accepted October 28, 2020. Date of current version January 7, 2021. This work was supported in part by the National Key Research and Development Program of China under Grant 2017YFB1300400, and in part by the National Nature Science Foundation of China under Grant U1609210. The Associate Editor coordinating the review process was Dr. Pekka Keränen. (*Corresponding authors: Yue Wang; Rong Xiong.*)

The authors are with the State Key Laboratory of Industrial Control and Technology, Zhejiang University, Hangzhou 310058, China (e-mail: wangyue@iipc.zju.edu.cn; rxiong@zju.edu.cn).

Digital Object Identifier 10.1109/TIM.2020.3034990