

Errata: Large-Area Visually Augmented Navigation for Autonomous Underwater Vehicles

- pg 150, element (3, 1) of \mathbf{K}_1 should read: $({}^j_k\mathbf{R}_{1,2} \sin \phi_{ik} + {}^j_k\mathbf{R}_{1,3} \cos \phi_{ik}) \sec \theta_{ik}$
- pg 163, the derivation of $\boldsymbol{\eta}_z$ in equation (B.6) should read:

$$\begin{aligned}
 \boldsymbol{\eta}_z &= \Lambda_{zz} \boldsymbol{\mu}_z \\
 &= (\Lambda_{\alpha\alpha} - \Lambda_{\alpha\beta} \Lambda_{\beta\beta}^{-1} \Lambda_{\beta\alpha}) \boldsymbol{\mu}_\alpha \\
 &= \Lambda_{\alpha\alpha} \boldsymbol{\mu}_\alpha - \Lambda_{\alpha\beta} \Lambda_{\beta\beta}^{-1} \Lambda_{\beta\alpha} \boldsymbol{\mu}_\alpha \\
 &= (\boldsymbol{\eta}_\alpha - \Lambda_{\alpha\beta} \boldsymbol{\mu}_\beta) - \Lambda_{\alpha\beta} \Lambda_{\beta\beta}^{-1} (\boldsymbol{\eta}_\beta - \Lambda_{\beta\beta} \boldsymbol{\mu}_\beta) \\
 &= \boldsymbol{\eta}_\alpha - \Lambda_{\alpha\beta} \boldsymbol{\mu}_\beta - \Lambda_{\alpha\beta} \Lambda_{\beta\beta}^{-1} \boldsymbol{\eta}_\beta + \Lambda_{\alpha\beta} \Lambda_{\beta\beta}^{-1} \Lambda_{\beta\beta} \boldsymbol{\mu}_\beta \\
 &= \boldsymbol{\eta}_\alpha - \Lambda_{\alpha\beta} \Lambda_{\beta\beta}^{-1} \boldsymbol{\eta}_\beta.
 \end{aligned}$$