Errata, revision 1.0

Location	**Original text**	**Replace with**
Page 21, last par.	accepted for publication in Robotics and Autonomous Systems	in Robotics and Autonomous Systems, Elsevier, 56:6, June 30, 2008, pp. 483-492
Page 24, 3rd par.	(IMU) compass,	(IMU), compass,
Page 37, 2nd par.	the central 2nd moments	best-fit bounding boxes
Page 47, 3rd par.	is needed as a building detector in Chapter 7,	is utilized in Chapter 5 to build the probabilistic semantic map needed in Chapter 7,
Page 50, last par.	features 1-3	features 1-2
Page 76, 2nd par. in 4.8	it can be beneficial to dist-inguish between stationary and movable objects in any mapping process.	it is generally beneficial to distinguish between stationary and movable objects.
Page 85, 1st row	detection is	detection (Section 4.5) is
Page 86, last par.	Markov property	Markov assumption
Page 88, 3rd par.	centre of the image plane	optical centre
Page 119, 1st row	$d = r_{\Delta}^{T} R^{-1} r_{\Delta}$	$d = \sqrt{r_{\Delta}^{T} R^{-1} r_{\Delta}}$
Page 119, 1st par.	and usually	since usually
Page 123, 2nd par.	the lines L_g^M	the group of lines L_g^M
Page 123, 2nd par., Page 124, 2nd row	L_a^N	L_a^i
Page 126, 1st row	in aerial	in local aerial