Correction to "On Gaussian Optimal Smoothing of Non-Linear State Space Models"

Simo Särkkä, *Member, IEEE* and Jouni Hartikainen

In the above technical note [1], some of the error values reported in Table I were incorrect. The corrected errors are reported in the Table I below. Although, the conclusions of the note remain unaffected, we apologize for any inconvenience caused to those who have been trying to reproduce the numerical results. The authors would like to thank Marc Deisenroth for pointing out the error.

REFERENCES

[1] S. Särkkä and J. Hartikainen, "On Gaussian optimal smoothing of non-linear state space models," *IEEE Transactions on Automatic Control*, vol. 55, no. 8, pp. 1938–1941, 2010.

TABLE I
TRACKING OF MANEUVERING TARGET: RMSE VALUES OF POSITION, VELOCITY AND TURN RATE ESTIMATES FOR THE TESTED FILTERS AND SMOOTHERS OVER 1000 SIMULATIONS.

Filter	RMSE(pos)	RMSE(vel)	RMSE(ω)
EKF	179.1	161.6	0.2195
UKF	40.9	22.7	0.0469
CDKF	40.5	22.6	0.0469
GHKF	40.1	22.4	0.0469
Smoother	RMSE(pos)	RMSE(vel)	RMSE(ω)
ERTS	160.2	125.1	0.2024
URTS	22.7	7.9	0.0123
CDRTS	22.1	7.7	0.0121
GHRTS	21.5	7.4	0.0119