頁碼	原文	更正
3-8行12	[eq:RT]	[3.9]
3-8行18	[eq:RT]	[3.9]
3-17行4	[eq:cross]。	[3.3]。
3-21末行	[eq:quaternionVirtual]	[3.21]
3-25首行	[eq:R2theta]	[3.17]
3-25行6	[eq:quaternion-to-rotation-matrix-derive]	[3.38
3-36 3.8 習題 3	[eq:rotate-with-quaternion]。	[3.33]。
4-5式4.6後一行	[eq:cross]	[3.3]
4-6行3	[eq:dR]	[4.8]
4-10式4.22前一行	[eq:rodridues]	[3.15]
4-10倒數第6行	[eq:R2theta]	[3.17]
4-14首行	[eq:lieAlgebraJacobian]	[4.27]
5-3行4	[eq:P2Pprime]	[5.3]
5-3行14`	[eq:P2Pprime]	[5.3]
5-6行8	[eq:intrinmatrix]	[5.6]
5-6到數第4行	[eq:cameraprojection]	[5.8]
5-9首行	[eq:distortion]	[5.10]
5-9首行	[eq:tangen]	[5.11]
6-3行2	[eq:slamproblem]	[2.5]
6-7行9	[eq:least-square]	[6.13]
6-13到數第8行	[eq:approximation]	[6.30]
6-14末行	[eq:6.24]	[6.34]
6-15行6	[eq:LM]	[6.35]
6-15行11	[eq:LM]	[6.35]
6-18到數第5行	[eq:least-square]	[6-13]
7-31行11	[eq:eight-point]	[7.13]
7-33行6	[eq:xltox2]	[7.25]

7-43倒數第3行	[eq:uv2xyz]	[7.41]
7-56數數第2行	[eq:pnp-solve-t]	[7.54]
8-19倒數第2行	[eq:jacobianofDirect]	[8.19]
8-28第6行	[eq:jacobianofDirect]	[8.19]
9-6第11行	[eq:bayes-estimator]	[9.6]
9-7倒數第4行	[eq:10-5]	[9.5]
9-8第8行	[eq:kalman-cov]	[9.16]
9-8末行	[eq:kalman-K]	[9.17]
9-15第4行	[eq:minimize-deltax]	[6.33]
9-15第倒數第5行	[eq:tangentbundleindetail]	[9.44]
9-18倒數第5行	[eq:BAcostfunction]	[9.42]
9-21首行	[eq:H-blocks]	[9.53]
9-21行5	[eq:HessianMatrix]	[9.50]
9-22行12	[eq:marginalization]	[9.59]
9-24行6	[eq:marginalization]	[9.59]
9-38習題1	[eq:kalman-K-another]	[9.25]
10-8行12	[eq:adjSE3]	[4.55]
7-43末行	[sec:se3-diff]	(7.41)
9-7行13	[sec:gauss-example]	(A.3)
9-15行3	[sec:6.2]	(6.2)
9-15行13	[sec:BA-vol]	(7.7.3)
12-6行8	[sec:epipolar-geometry]	(7.3)
12-29行10	[sec:join-point-cloud]	(5.4.2)