29 April 2021

Kevin M. Lynch, Ph.D.

Editor-in-Chief, *IEEE Transactions on Robotics (T-RO)*

Dear Dr. Lynch:

Please consider the enclosed manuscript, “Unified Robot and Inertial Sensor Self-Calibration using Fast Sequential Trajectory Optimization” for publication in *TR-O*. This novel work investigates a new method which unites two previously unrelated calibration problems in robotics into one fast self-calibration step. Furthermore, our method uses a new trajectory optimization method which is useful for planning optimal trajectories over long time scales. The results of our study are valuable to researchers who wish to identify robot parameters, researchers who work with inertial sensors, and researchers who study optimal trajectory planning. With the other authors of this manuscript, I believe this paper will be a valuable contribution to the field of robotics that will interest the readers of *TR-O.*

This manuscript is the original work of the authors and has not been copyrighted, published, submitted, or accepted for publication elsewhere. The authors have no conflicts of interest to disclose.

Sincerely,

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