Errata:
Stick It! Articulated Tracking using Spatial Rigid Object Priors

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December 28, 2015

This document provides a list of known issues for the paper *"Stick It! Articulated Tracking using Spatial Rigid Object Priors"* [1]. Please contact Søren Hauberg in case you find further mistakes.

- Equation 3 of the paper states that

$$p_{\text{proj}}(\theta_t|\theta_{t-1}) = \text{proj}_{\mathcal{M}}[\mathcal{N}(F(\theta_t)|F(\theta_{t-1}), \Sigma)]. \tag{1}$$

  This distribution is obviously not normalized correctly, and like other distributions discussed in the paper it is only stated up to an unknown constant:

$$p_{\text{proj}}(\theta_t|\theta_{t-1}) \propto \text{proj}_{\mathcal{M}}[\mathcal{N}(F(\theta_t)|F(\theta_{t-1}), \Sigma)]. \tag{2}$$

  I apologize for this typo.

- Similar comments hold for Eq. 8, which should be

$$p_{\text{stick3d}}(\theta_t|\theta_{t-1}) \propto \text{proj}_{\mathcal{M}}[\mathcal{N}(F(\theta_t)|\mu, \Sigma)]. \tag{3}$$

References

[1] Søren Hauberg and Kim S. Pedersen, *Stick It! Articulated Tracking using Spatial Rigid Object Priors*, Asian Conference on Computer Vision (ACCV), 2010.