Corrections & amendments

Publisher Correction: Moving event detection from LiDAR point streams

Correction to: <i>Nature Communications</i> https://doi.org/10.1038/s41467-023-44554-8, published online 06 January 2024	Huajie Wu 🕏, Yihang Li, Wei Xu, Fanze Kong & Fu Zhang
nttps://doi.org/10.1038/s41467-024-46400-x	The Authors provide the corrected text for the following issues marked as points A and B, A. Error location: Author list
Published online: 05 March 2024	Error: Missing symbol of equal contribution specifying the equal author contributions for the first <huajie wu=""> and second author <yihang li="">.</yihang></huajie>
Check for updates	 Correction text: The original version of this Published Article omitted the symbol for the equal Authors contribution of the first two authors, <huajie wu=""> and <yihang li="">. The correct way to display the Authors list is < Huajie Wu^{1,2}, Yihang Li^{1,2}, Wei Xu¹, Fanze Kong¹, Fu Zhang¹> and a sentence should be added <²These authors contributed equally>.</yihang></huajie> B. Error location: Text Error: Scientific error in multiple sentences, missing word ref. in the points 1–4 (see below) Correction text:
	 The original version of this Article contained an error in <location: 2,="" column,="" in="" introduction="" last="" left="" paragraph="" pg.="" second="" the="">, which incorrectly read <ln addition<sup="">19, relies on a future frame for detecting moving objects, which exacerbates the delay further>. The correct version is <ln 19="" a="" addition,="" delay="" detecting="" exacerbates="" for="" frame="" further.="" future="" moving="" objects="" on="" ref.="" relies="" the="" which=""></ln></ln></location:> The original version of this Article contained an error in <location: 2,="" column,="" in="" introduction="" last="" left="" paragraph="" pg.="" second="" the="">, which incorrectly read '<moreover<sup>21,22,23, are offline systems that require all LiDAR frames for occupancy map construction.>. The correct version is </moreover<sup></location:> Moreover, refs. 21,22,23 are offline systems that require all LiDAR frames for occupancy map construction.> The original version of this Article contained an error in <location: 9,="" column,="" discussion:="" in="" paragraph="" pg.="" right="" second="" the="">, which incorrectly read <ln as<sup="" contrast,="" learning-based="" methods,="" or="" performance="" such="" the="">30, could drop considerably if the test dataset is different from the training dataset.>. The correct version is <ln 30,="" as="" considerably="" contrast,="" could="" dataset="" dataset.="" different="" drop="" from="" if="" is="" learning-based="" methods,="" or="" performance="" ref.="" such="" test="" the="" training="">.</ln></ln></location:> The original version of this Article contained an error in <location: 9,="" column,="" discussion:="" in="" paragraph="" pg.="" right="" second="" the="">, which incorrectly read <ln 30,="" as="" considerably="" contrast,="" could="" dataset="" dataset.="" different="" drop="" from="" if="" is="" learning-based="" methods,="" or="" performance="" ref.="" such="" test="" the="" training="">.</ln></location:> The original version of this Article contained an error in <location: 9,="" column,="" discussion:="" in="" paragraph="" pg.="" right="" second="" the="">, which incorrectly read <likewise, in<sup="" map="" occupancy="" the="" used="">20-23 can address this ambiguity by distinguishing the unseen areas from seen ones.> The correct version is <likewise, 20–23="" a<="" address="" can="" in="" map="" occupancy="" refs.="" td="" the="" this="" used=""></likewise,></likewise,></location:>
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