

## Calibration results

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### Camera-system parameters:

cam0 (/prophesee/left/events):

type: <class 'aslam\_cv.libaslam\_cv\_python.DistortedPinholeCameraGeometry'>

distortion: [-0.04942202 0.07765947 0.00087733 -0.00152492] +- [0.00102218 0.00223194 0.0000855 0.00005846]

projection: [1027.73067754 1027.22172713 631.5864158 368.42668839] +- [0.16555401 0.16466557 0.01420139 0.2165578 ]

reprojection error: [0.000037, -0.000036] +- [0.550478, 0.508737]

cam1 (/prophesee/right/events):

type: <class 'aslam\_cv.libaslam\_cv\_python.DistortedPinholeCameraGeometry'>

distortion: [-0.05605906 0.08282759 0.00182783 -0.00003058] +- [0.00109421 0.00250479 0.00007684 0.00005572]

projection: [1027.63970333 1027.51509453 634.56849554 370.16403364] +- [0.15935812 0.15434859 0.00421135 0.07427198]

reprojection error: [0.000038, -0.000049] +- [0.623286, 0.583488]

cam2 (/ovc/left/image\_mono/compressed):

type: <class 'aslam\_cv.libaslam\_cv\_python.DistortedPinholeCameraGeometry'>

distortion: [-0.39869676 0.16445166 -0.00013072 0.0015014 ] +- [0.0006067 0.00108183 0.00005372 0.00003907]

projection: [1053.89781698 1053.29007318 669.2007802 335.62603231] +- [0.15758798 0.15637277 0.00868723 0.20704185]

reprojection error: [0.000078, 0.000050] +- [0.834890, 0.768620]

cam3 (/ovc/right/image\_mono/compressed):

type: <class 'aslam\_cv.libaslam\_cv\_python.DistortedPinholeCameraGeometry'>

distortion: [-0.39279013 0.15002956 -0.00029922 0.00140275] +- [0.00048136 0.0007414 0.00005688 0.00003467]

projection: [1048.73110068 1048.45307196 670.54497331 328.28442879] +- [0.16050355 0.15471907 0.00738315 0.23486538]

reprojection error: [-0.000008, 0.000098] +- [0.836581, 0.775466]

cam4 (/ovc/rgb/image\_color/compressed):

type: <class 'aslam\_cv.libaslam\_cv\_python.DistortedPinholeCameraGeometry'>

distortion: [-0.41345455 0.18264947 -0.00018117 0.00128141] +- [0.00085262 0.00207314 0.00005767 0.00004956]

projection: [1254.91957248 1254.34584742 644.18704876 367.23280902] +- [0.05792623 0.05740512 0.00444547 0.02614386]

reprojection error: [-0.000037, -0.000177] +- [0.839714, 0.930685]

baseline T\_1\_0:

q: [-0.00106631 0.00291852 -0.00041539 0.99999509] +- [0.00021843 0.00007497 0.00003986]

t: [-0.12019679 0.00100092 0.00024878] +- [0.00005225 0.00004725 0.00016714]

baseline T\_2\_1:

q: [ 0.00131551 -0.00410288 -0.00500743 0.99997818] +- [0.00021267 0.00006494 0.00003828]

t: [0.12026585 0.06909337 0.00283501] +- [0.00004853 0.00004487 0.00016111]

baseline T\_3\_2:

q: [ 0.00023849 -0.00102623 0.00024534 0.99999941] +- [0.00033515 0.00005889 0.00003381]

t: [-0.11999477 -0.00005942 0.00119375] +- [0.00004411 0.00004161 0.00016121]

baseline T\_4\_3:

q: [0.0018772 0.00237582 0.00040161 0.99999534] +- [0.00023591 0.00006103 0.00003715]

t: [0.08845123 0.00610687 0.0011487 ] +- [0.00004409 0.00004237 0.00012586]

Target configuration

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Type: aprilgrid

Tags:

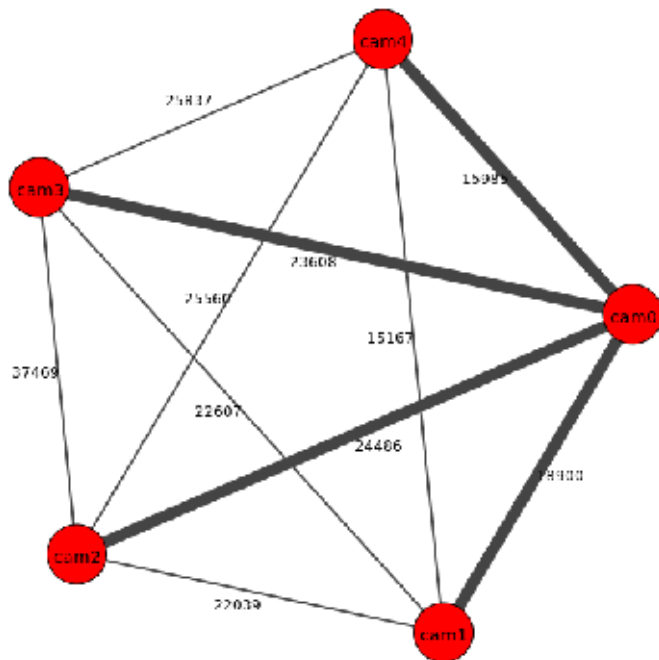
Rows: 5

Cols: 7

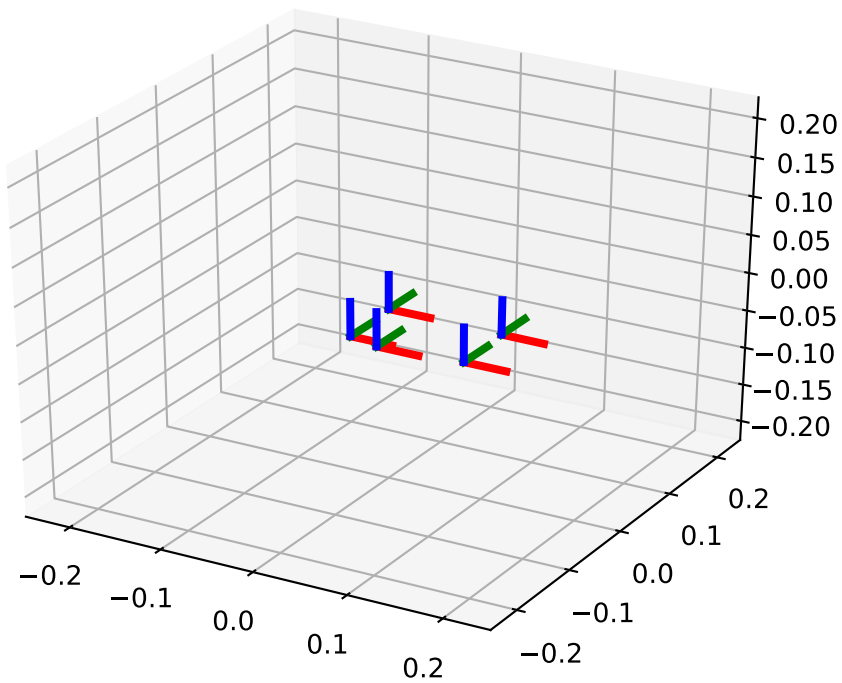
Size: 0.04 [m]

Spacing 0.01 [m]

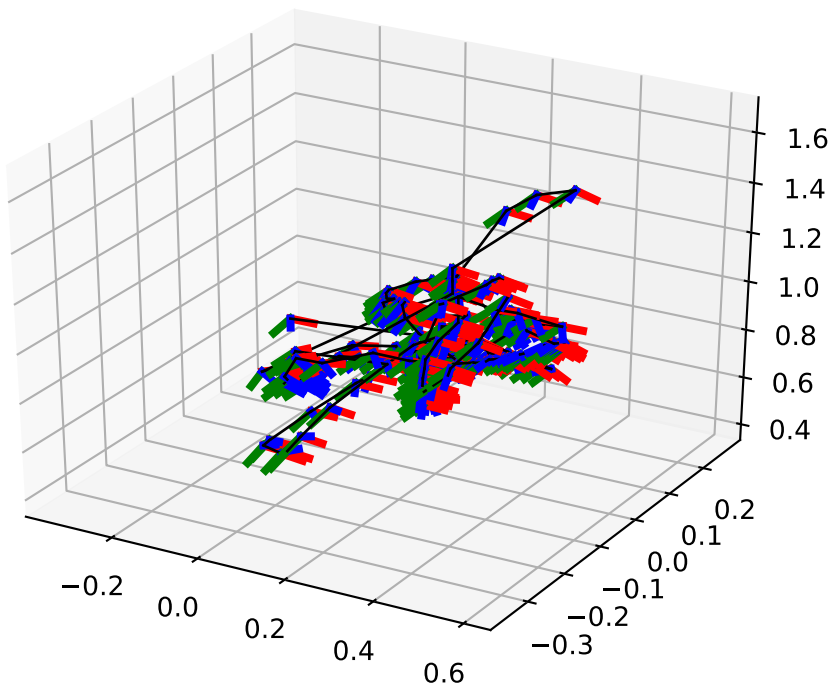
# Inter-camera observations graph (edge weight=#mutual obs.)



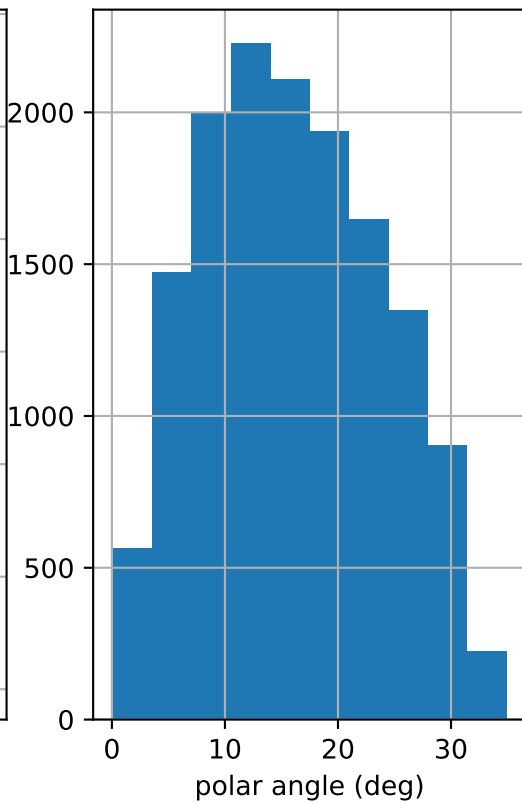
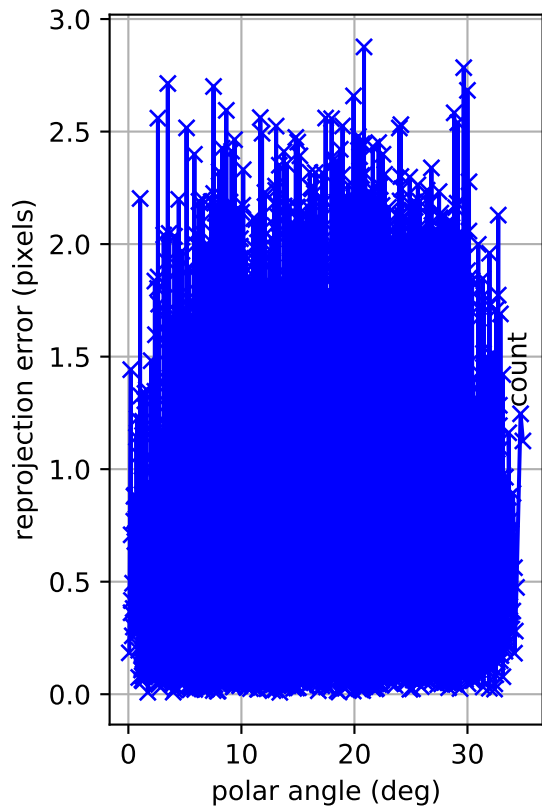
# camera system



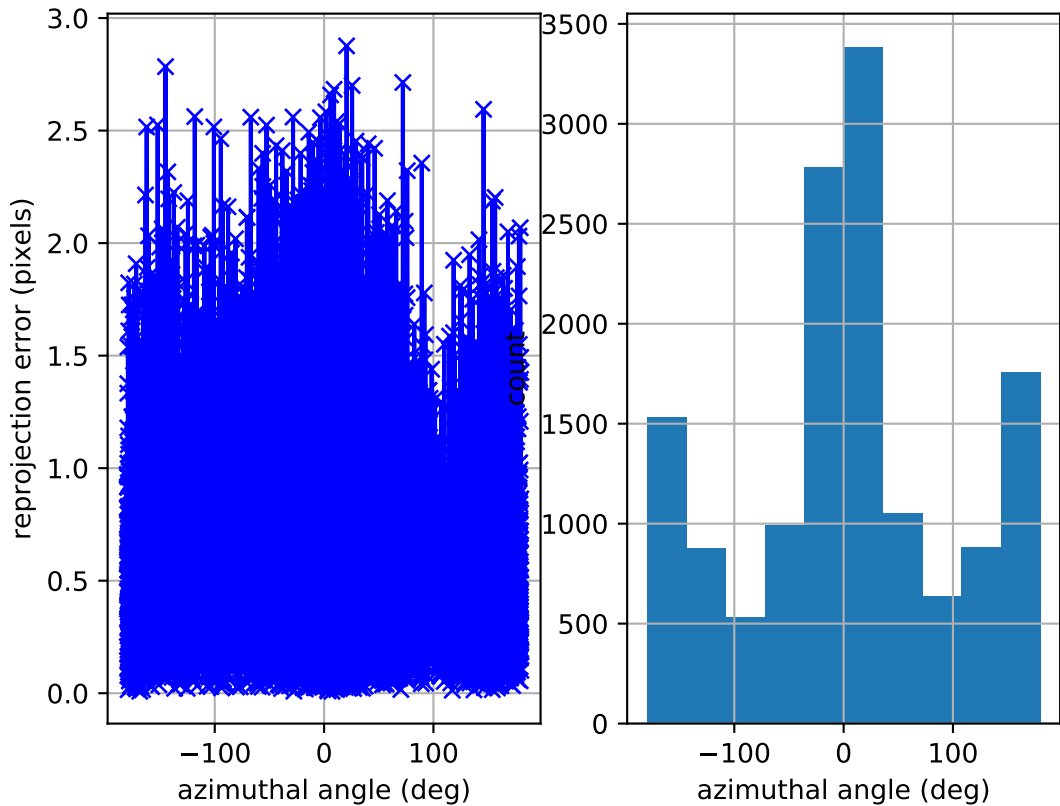
cam0: estimated poses



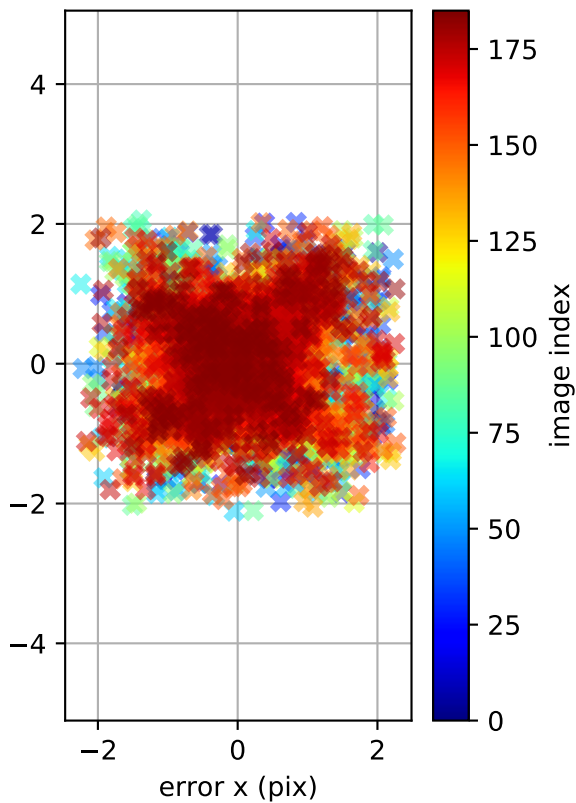
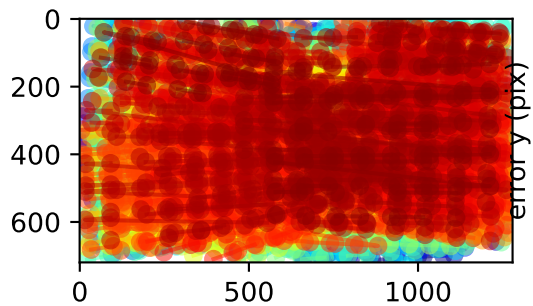
cam0: polar error



cam0: azimuthal error

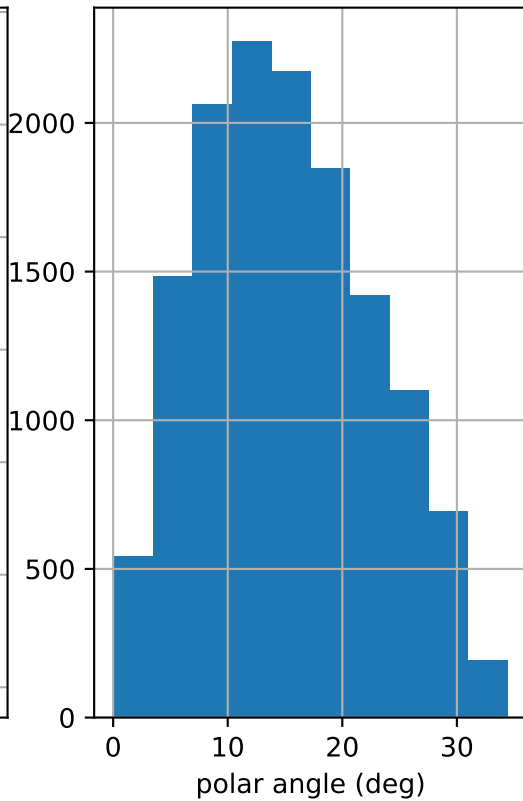
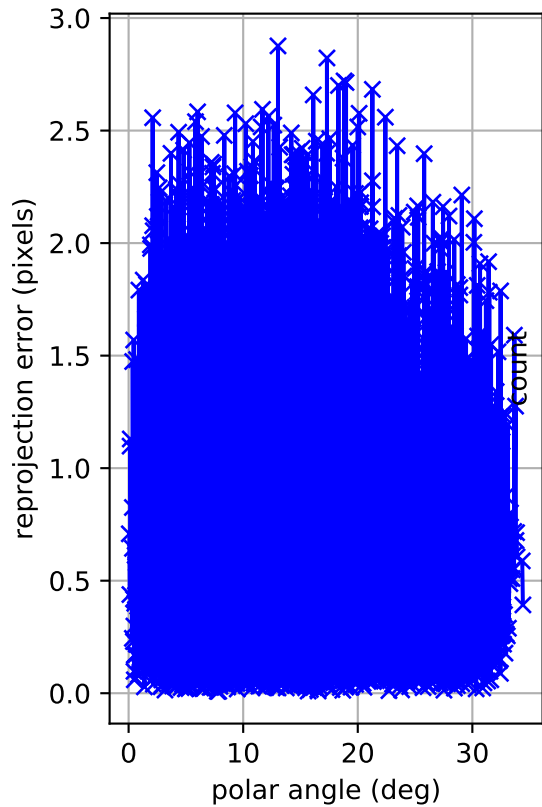


# cam0: reprojection errors

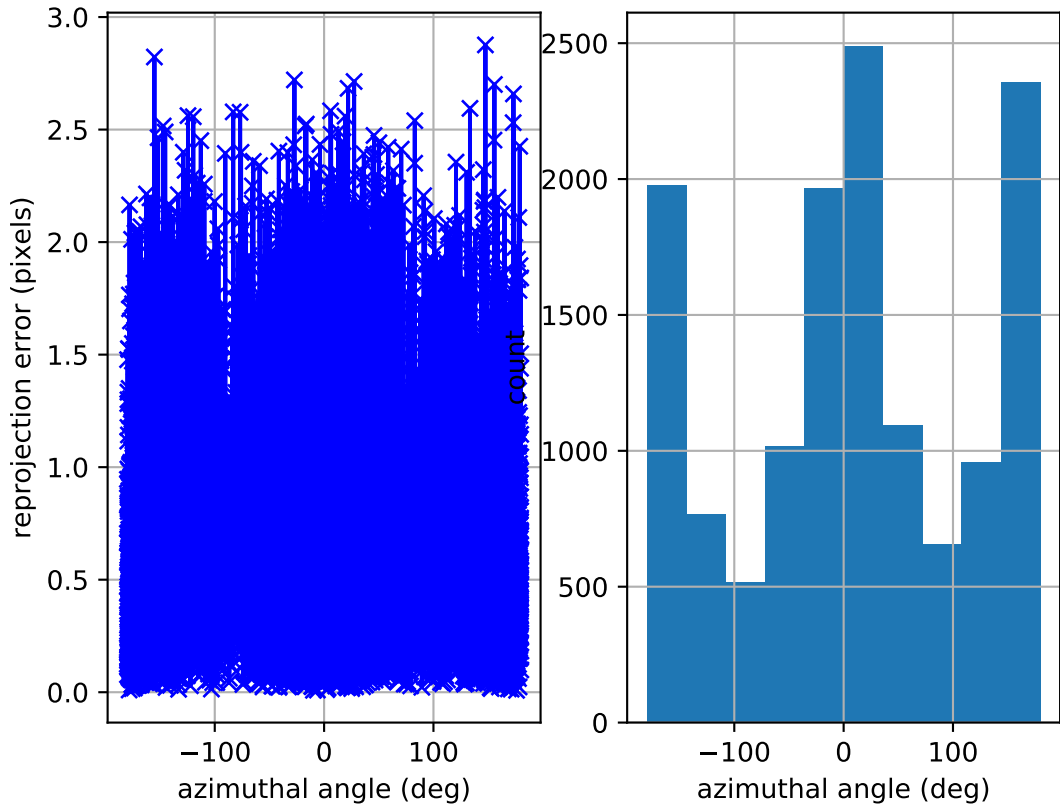




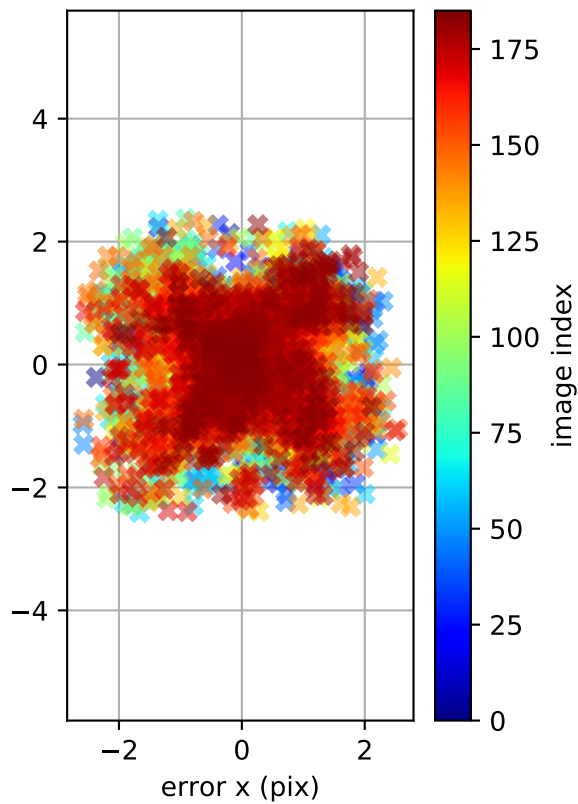
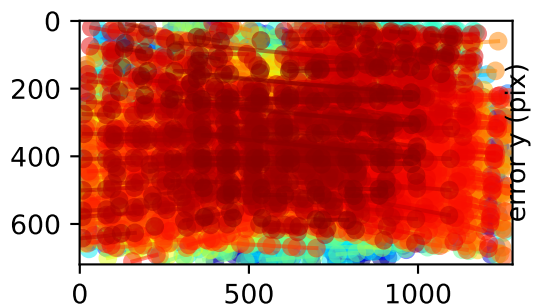
cam1: polar error



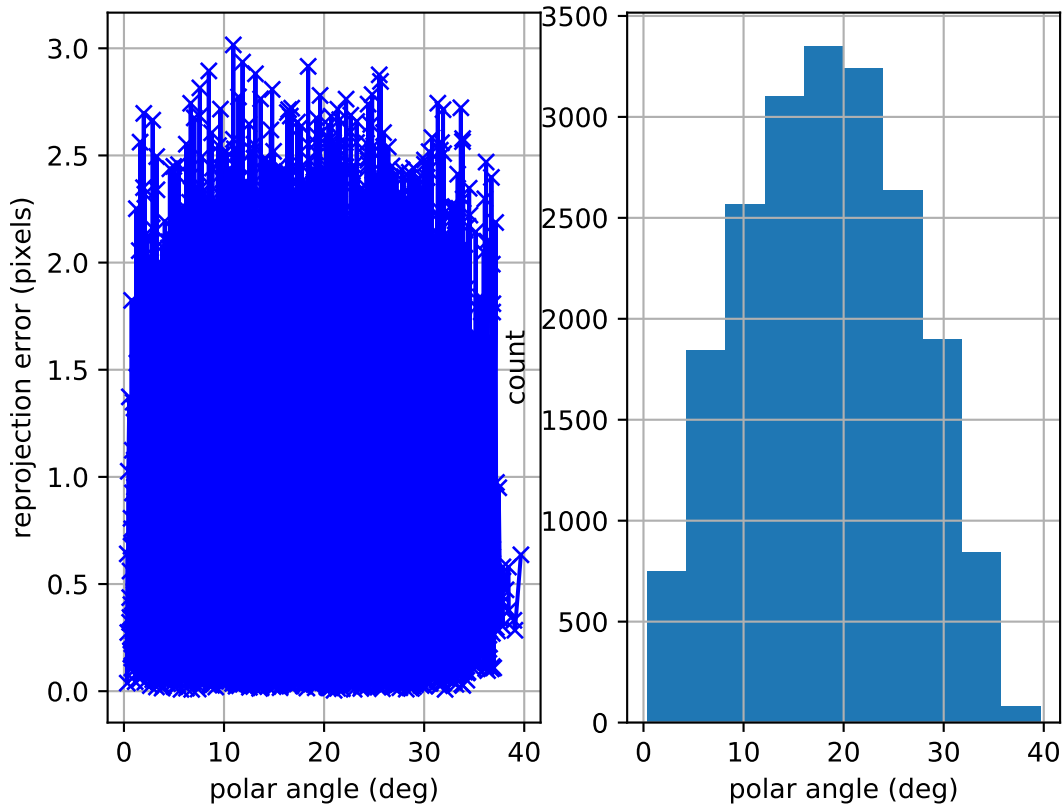
cam1: azimuthal error



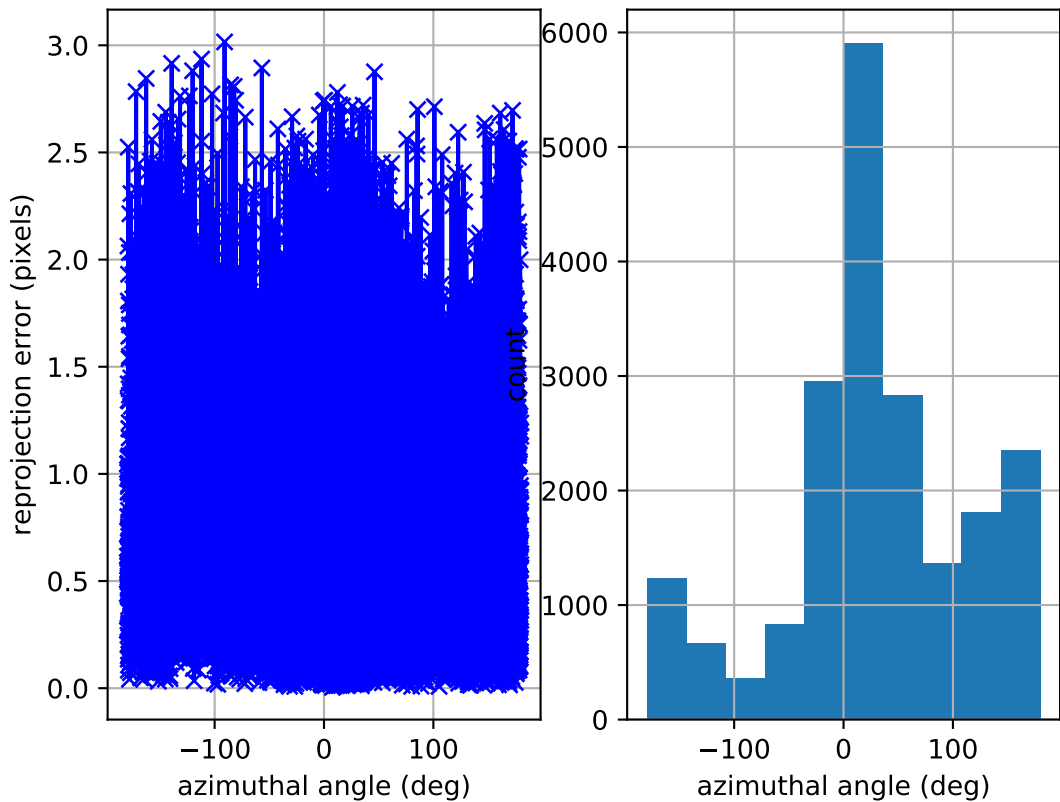
# cam1: reprojection errors



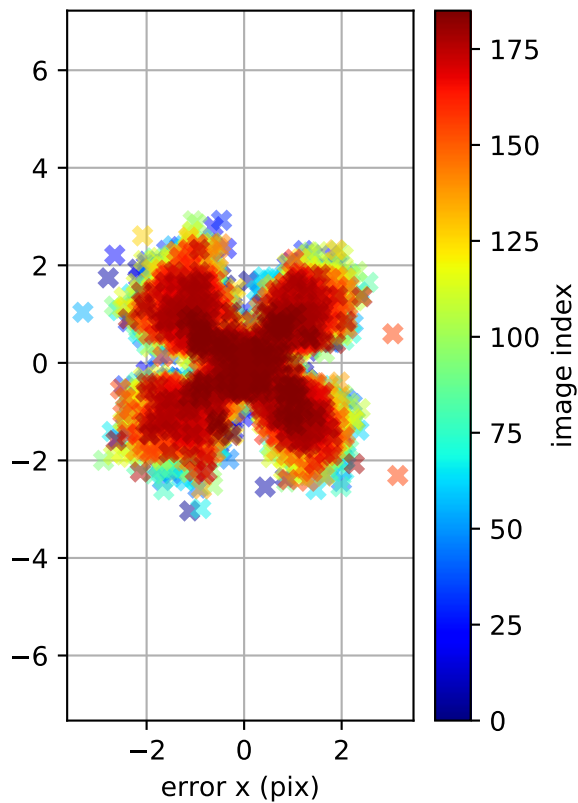
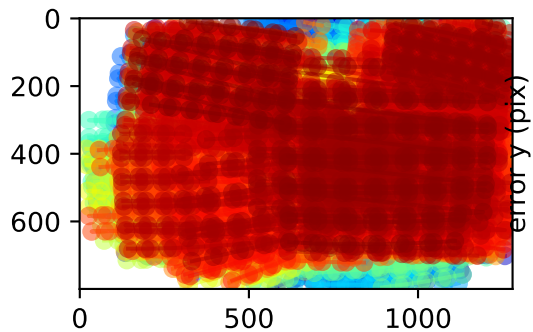
cam2: polar error



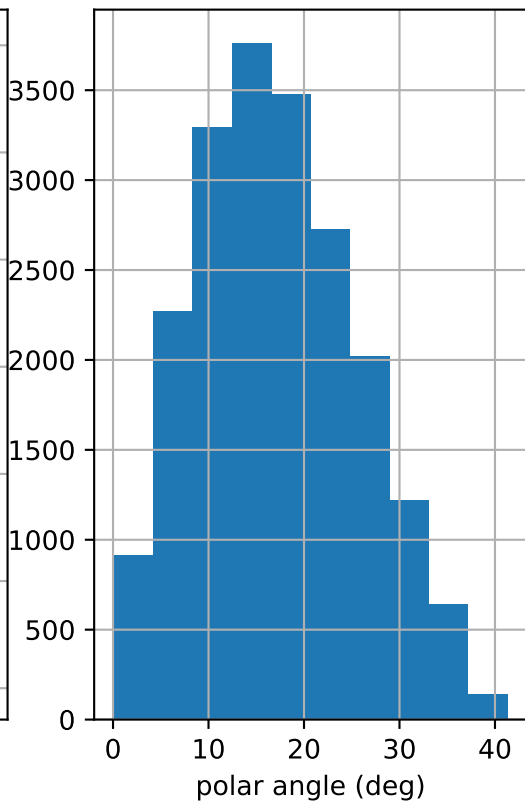
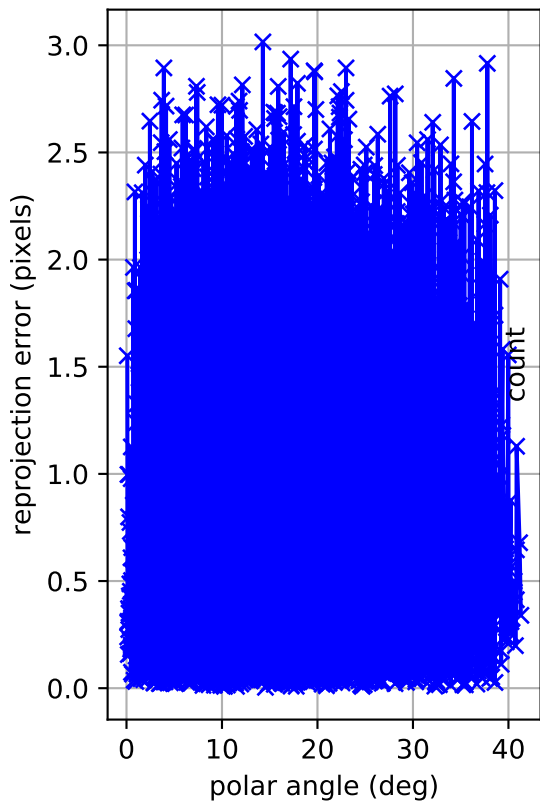
cam2: azimuthal error



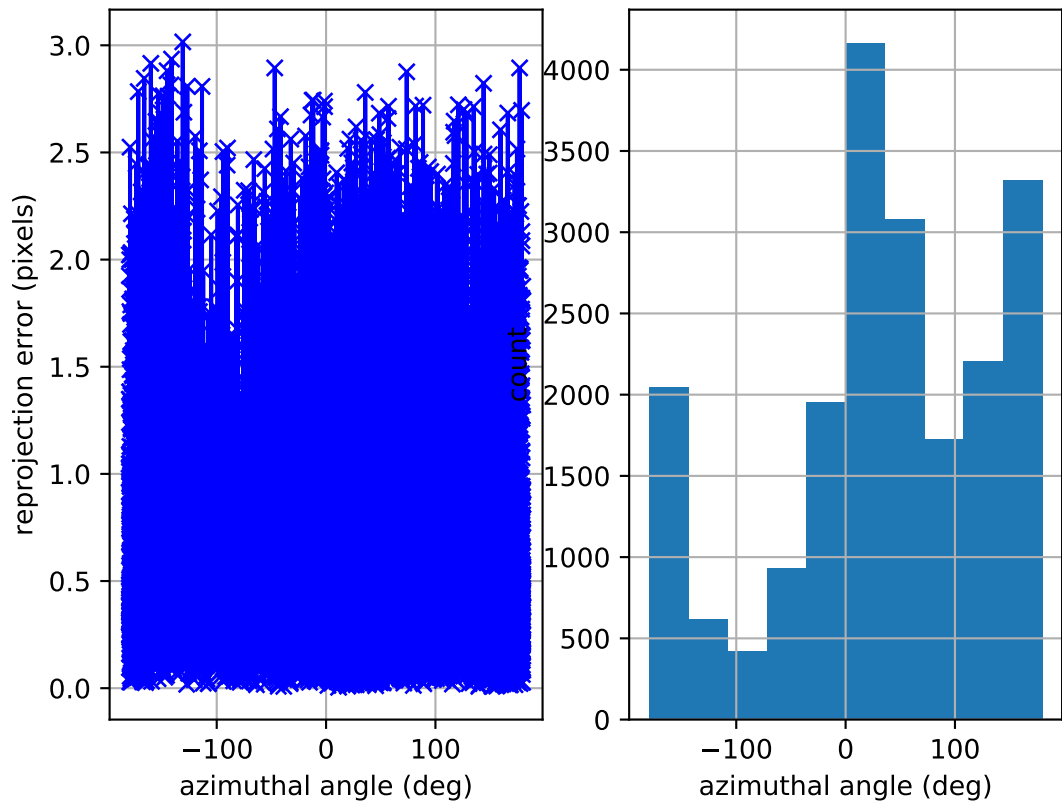
# cam2: reprojection errors



cam3: polar error

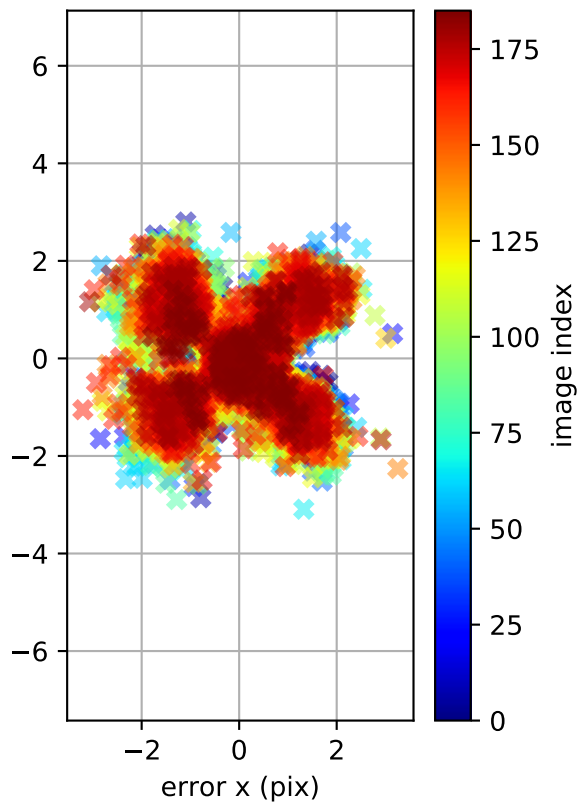
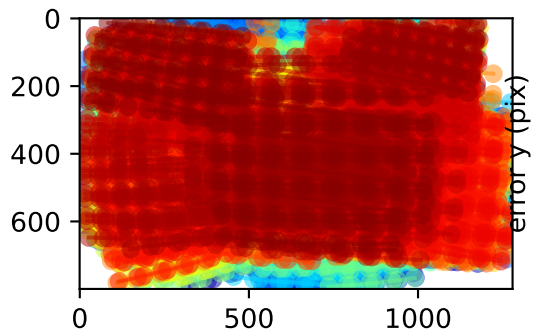


cam3: azimuthal error

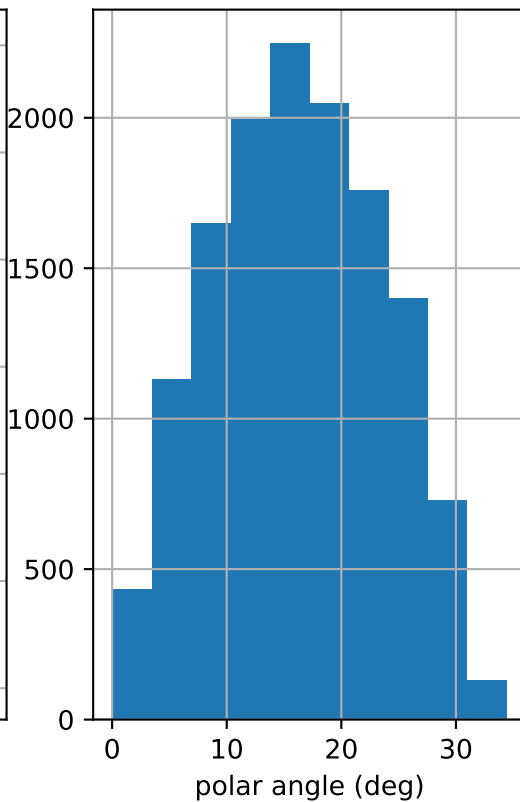
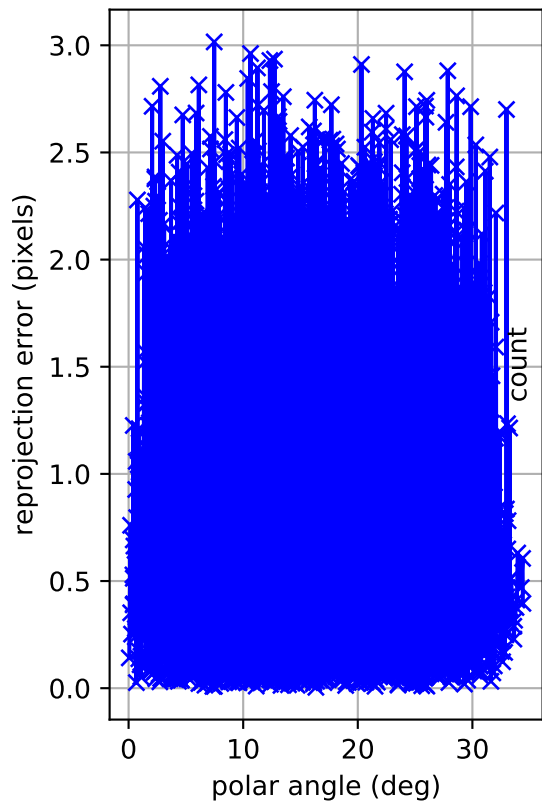




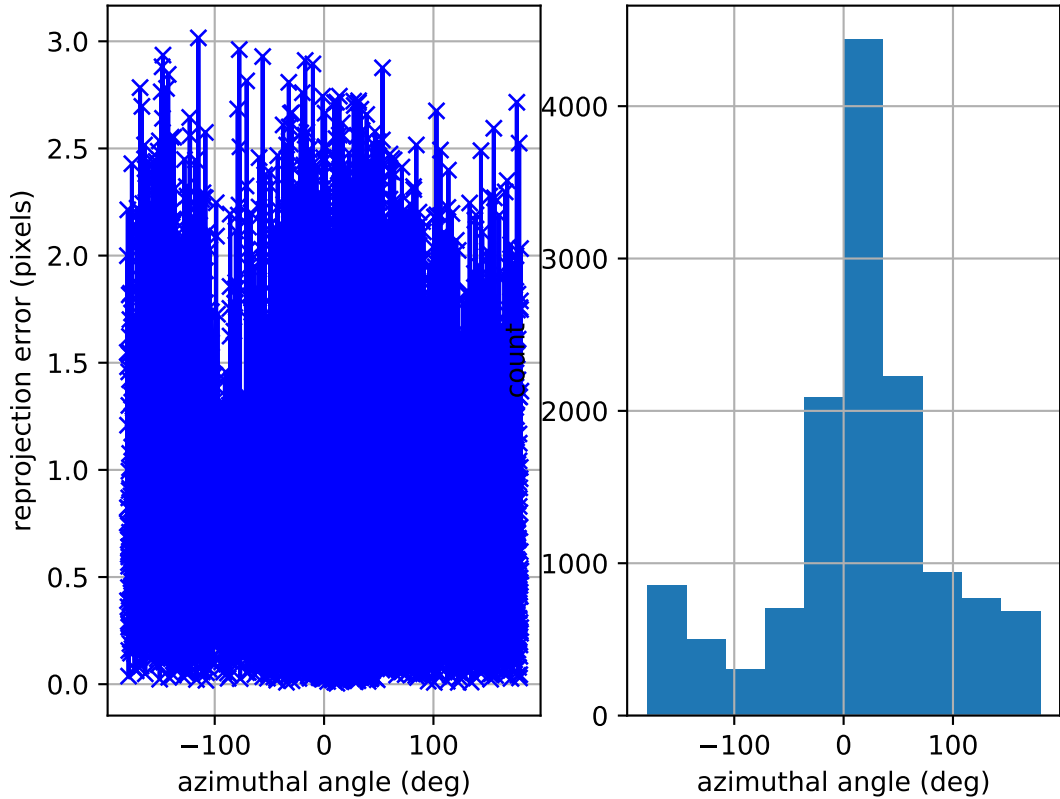
# cam3: reprojection errors



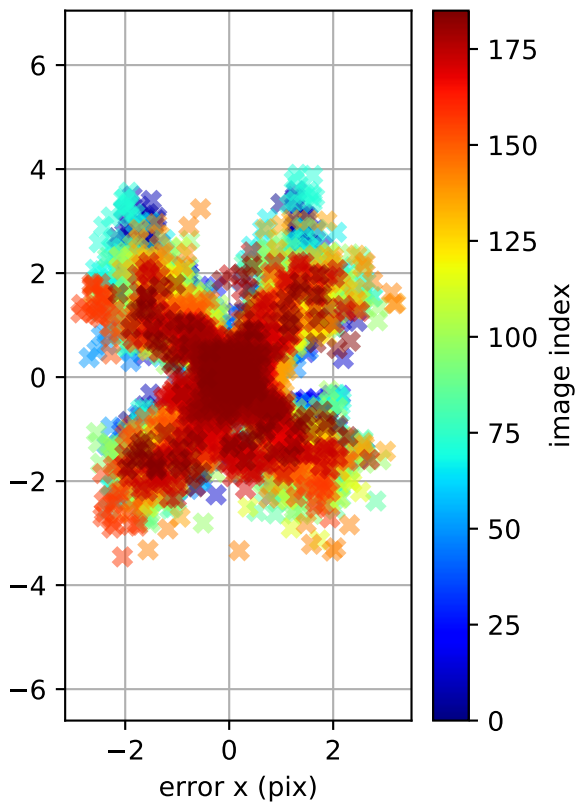
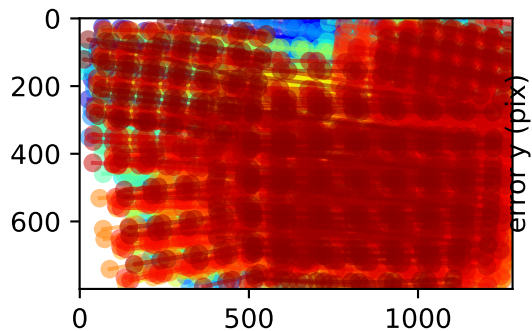
cam4: polar error



cam4: azimuthal error



# cam4: reprojection errors



# Location of removed outlier corners

