

## Calibration results

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### Camera-system parameters:

#### cam0 (/prophesee/left/events):

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

distortion: [-0.04940616 0.08712177 0.00039218 -0.00131025] +- [0.00093987 0.00203736 0.00007963 0.00005537]  
projection: [1031.88399229 1031.48192315 634.29808475 366.39105342] +- [0.12112506 0.12783928 0.00570335 0.12022572]

reprojection error: [0.000159, -0.000075] +- [0.507526, 0.430341]

#### cam1 (/prophesee/right/events):

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

distortion: [-0.05616592 0.0894742 0.0013979 -0.00038158] +- [0.00095815 0.00209754 0.00007619 0.00005302]  
projection: [1031.36879978 1031.06491961 634.87768084 367.62546105] +- [0.12462947 0.12894203 0.0024552 0.08284658]

reprojection error: [0.000179, -0.000085] +- [0.616755, 0.576574]

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

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

distortion: [-0.39637347 0.16418491 -0.00003184 0.00070978] +- [0.00054185 0.00099088 0.00005319 0.00003502]  
projection: [1057.54595775 1057.44953393 674.25647314 335.82907046] +- [0.11090686 0.11149445 0.02780577 0.19278486]

reprojection error: [0.000289, -0.000116] +- [0.173944, 0.142095]

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

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

distortion: [-0.39388342 0.15602662 -0.00032142 0.00125614] +- [0.00044318 0.00071406 0.0000493 0.00003341]  
projection: [1052.19472492 1052.61834484 670.97169632 329.43402809] +- [0.10800749 0.10929088 0.00965433 0.1962022 ]

reprojection error: [0.000395, -0.000231] +- [0.192986, 0.144990]

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

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

distortion: [-0.41688044 0.18993708 0.00026017 0.00014251] +- [0.00072549 0.00177699 0.00005337 0.00003655]  
projection: [1264.00083888 1263.57598006 650.76484047 366.8843554 ] +- [0.11387152 0.11422361 0.0083229 0.08554764]

reprojection error: [0.000238, -0.000041] +- [0.369283, 0.190696]

#### baseline T\_1\_0:

q: [-0.00088823 0.00170184 -0.00037513 0.99999809] +- [0.00011603 0.0000511 0.00003795]

t: [-0.12022098 0.00090584 -0.00011366] +- [0.00003072 0.00002951 0.00009119]

baseline T\_2\_1:

q: [-0.00018103 -0.00191883 -0.00512067 0.99998503] +- [0.00022657 0.00005521 0.00003544]

t: [0.12020811 0.06924435 0.00412882] +- [0.00002807 0.00002668 0.00008576]

baseline T\_3\_2:

q: [-0.00018475 -0.00331257 0.00020039 0.99999448] +- [0.00028252 0.00005278 0.00003059]

t: [-0.12002363 -0.00012843 0.00110524] +- [0.00002431 0.00002165 0.00007801]

baseline T\_4\_3:

q: [0.00252245 0.00515898 0.00035182 0.99998345] +- [0.00023713 0.00003798 0.00003015]

t: [0.08881793 0.00620989 0.00325709] +- [0.00002295 0.00002064 0.00007297]

Target configuration

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Type: aprilgrid

Tags:

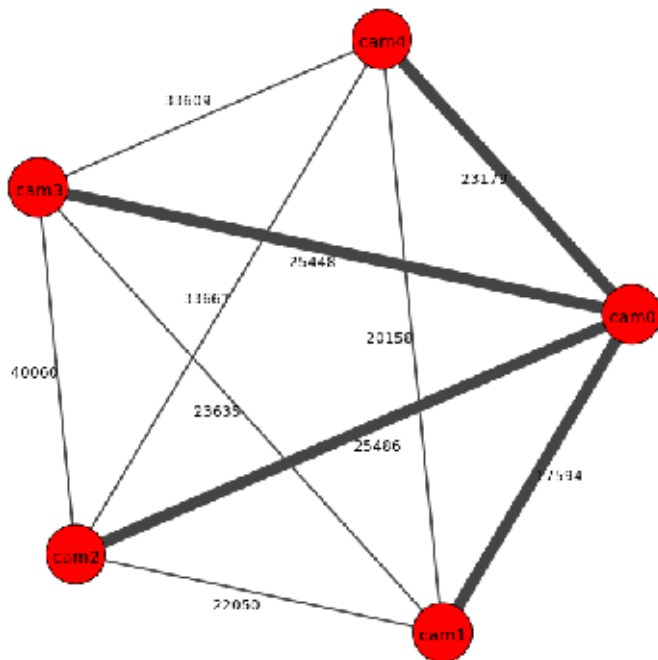
Rows: 5

Cols: 7

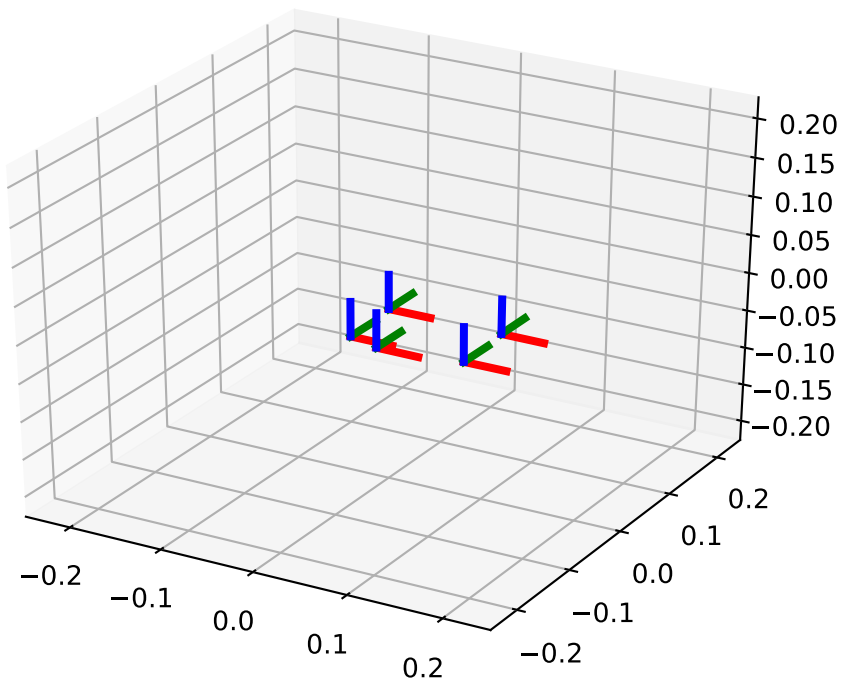
Size: 0.04 [m]

Spacing 0.01 [m]

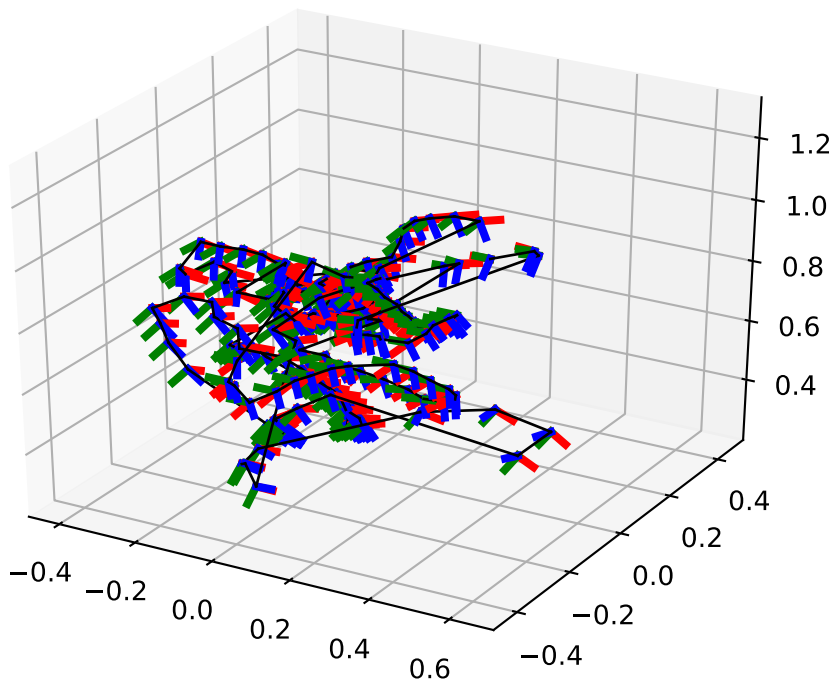
Inter-camera observations graph (edge weight=#mutual obs.)



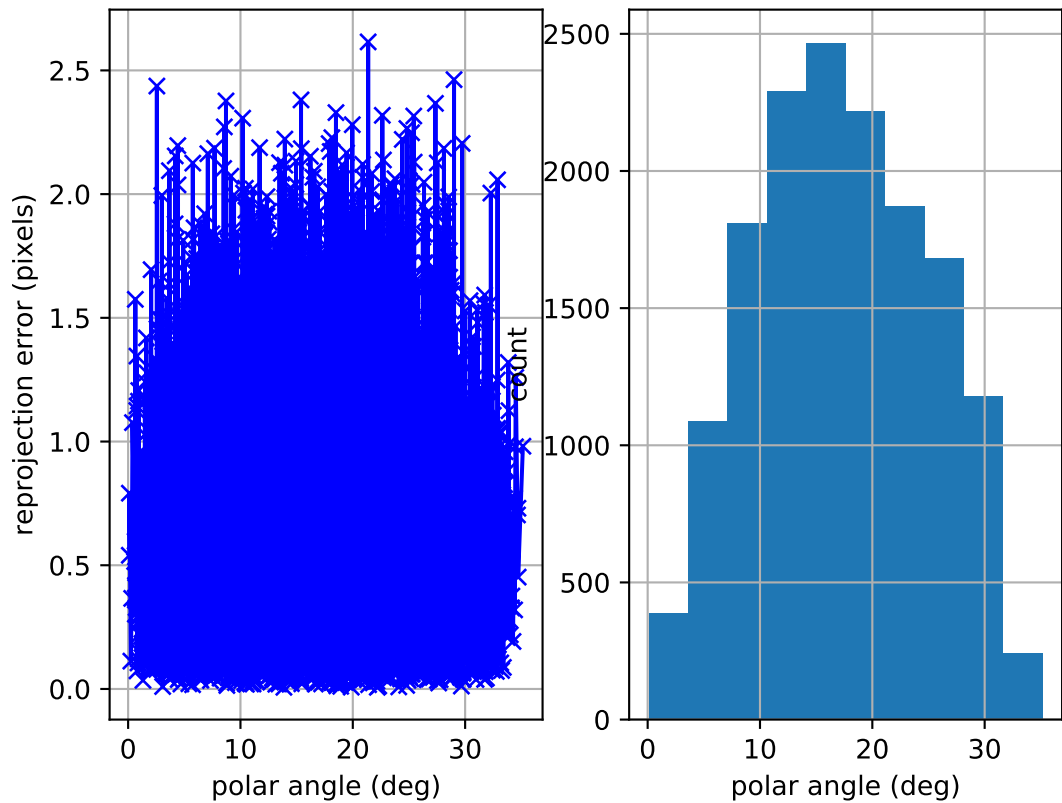
camera system



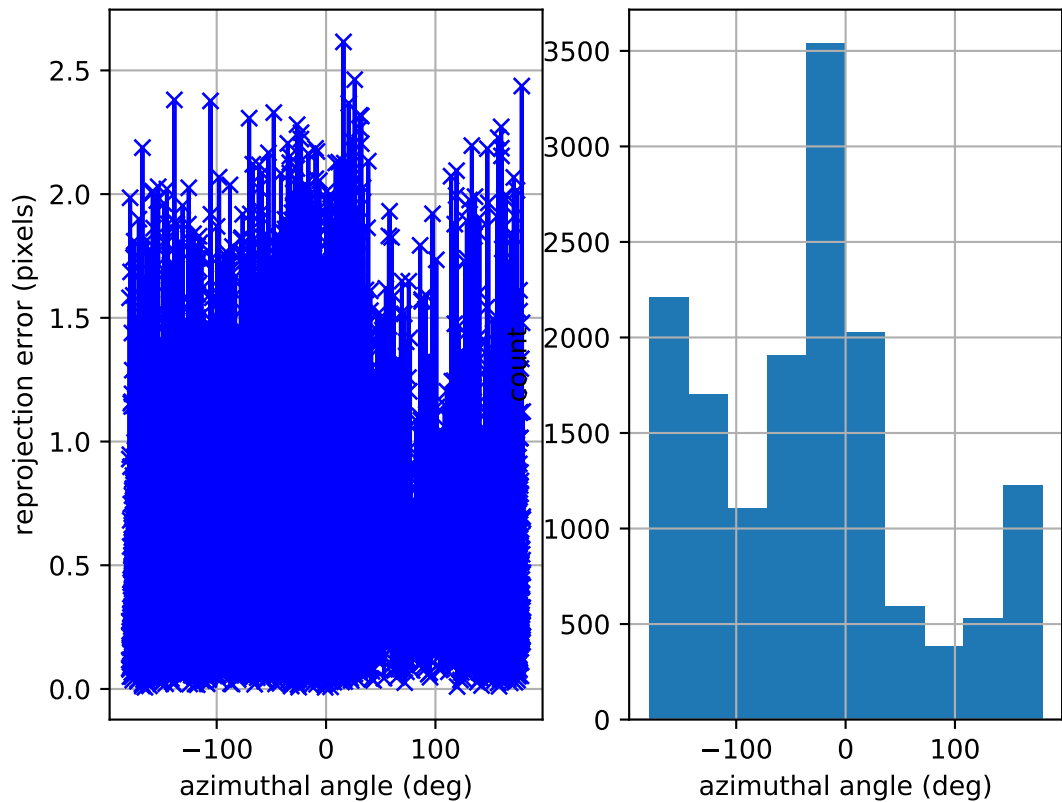
cam0: estimated poses



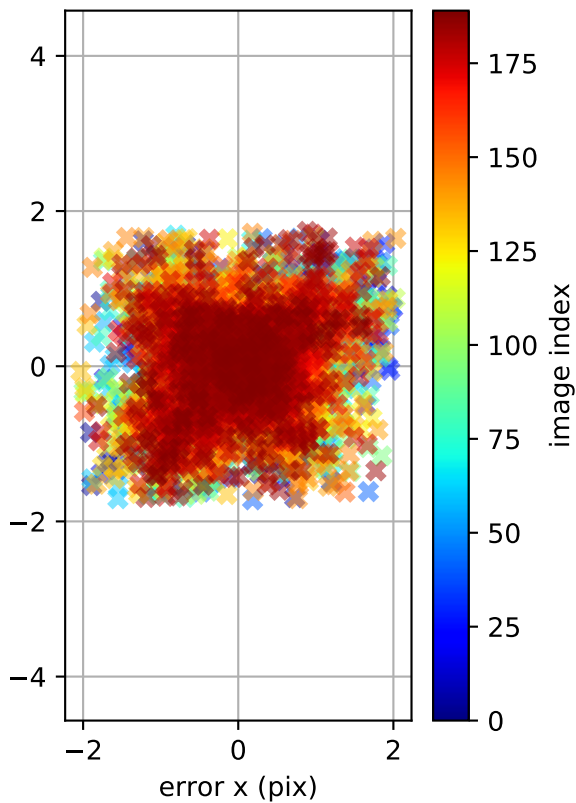
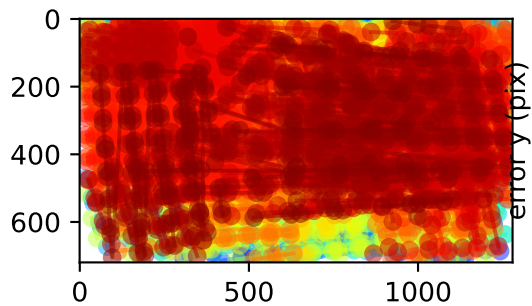
cam0: polar error



cam0: azimuthal error

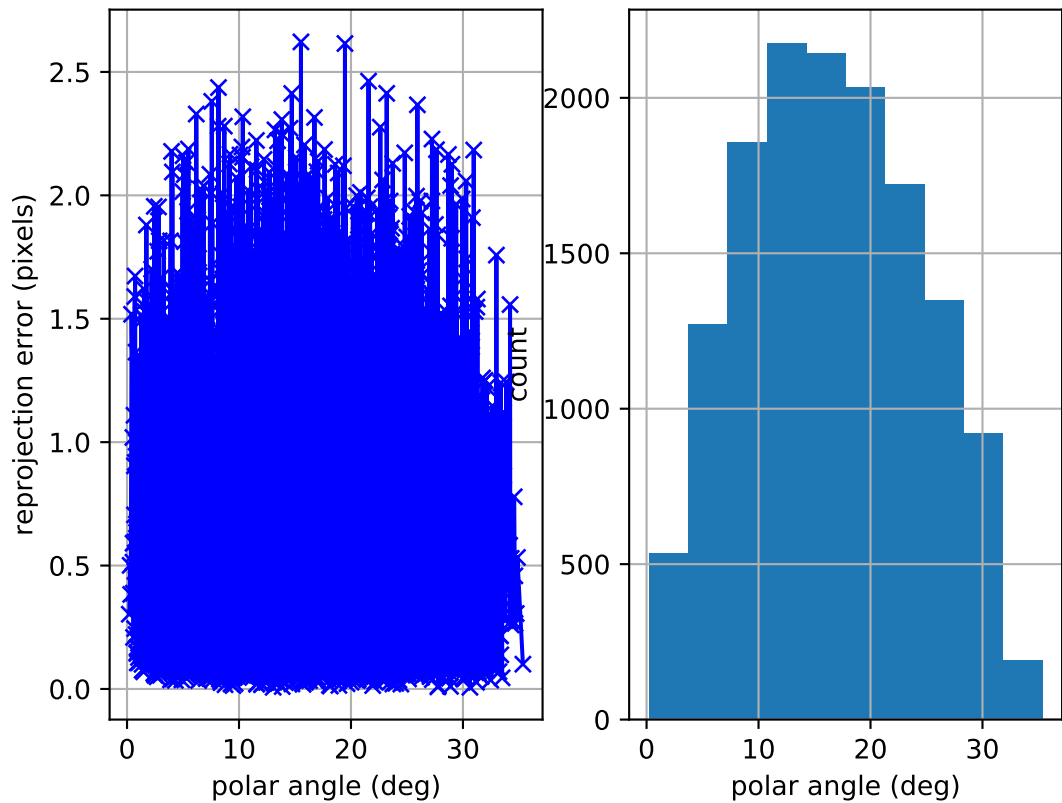


# cam0: reprojection errors

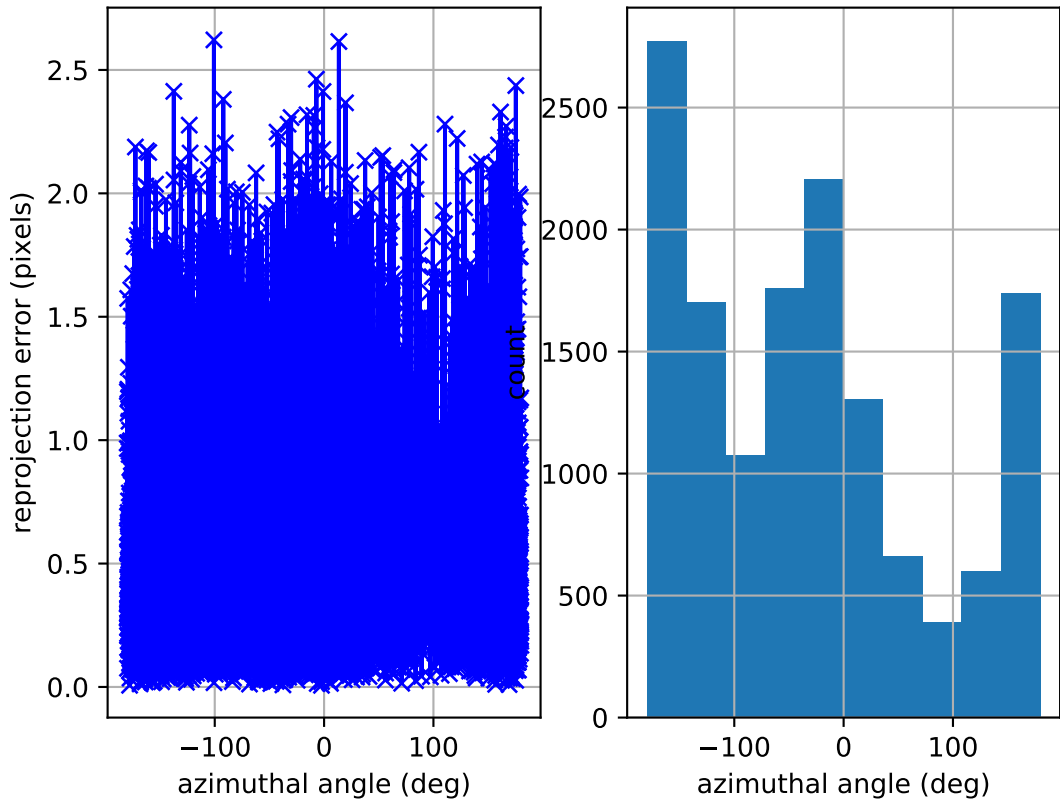




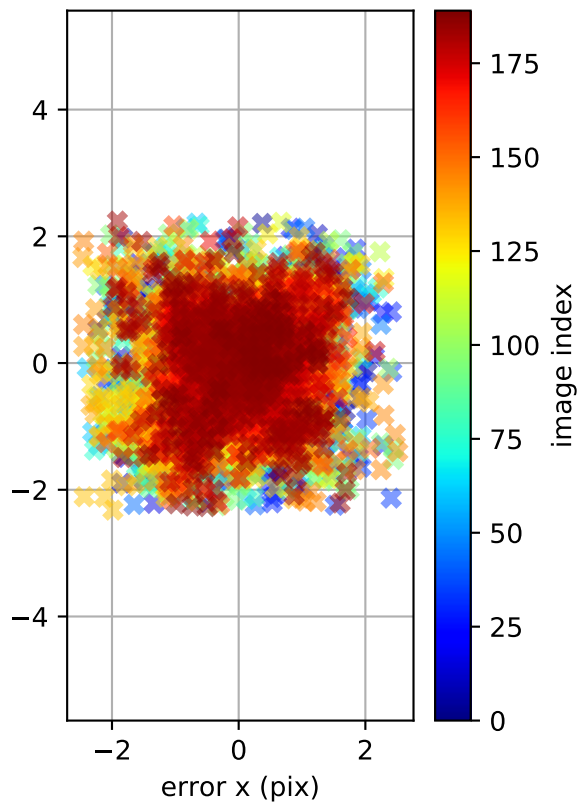
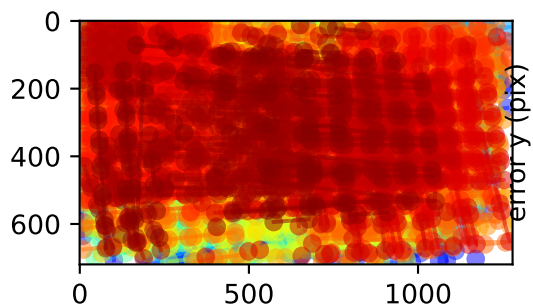
cam1: polar error



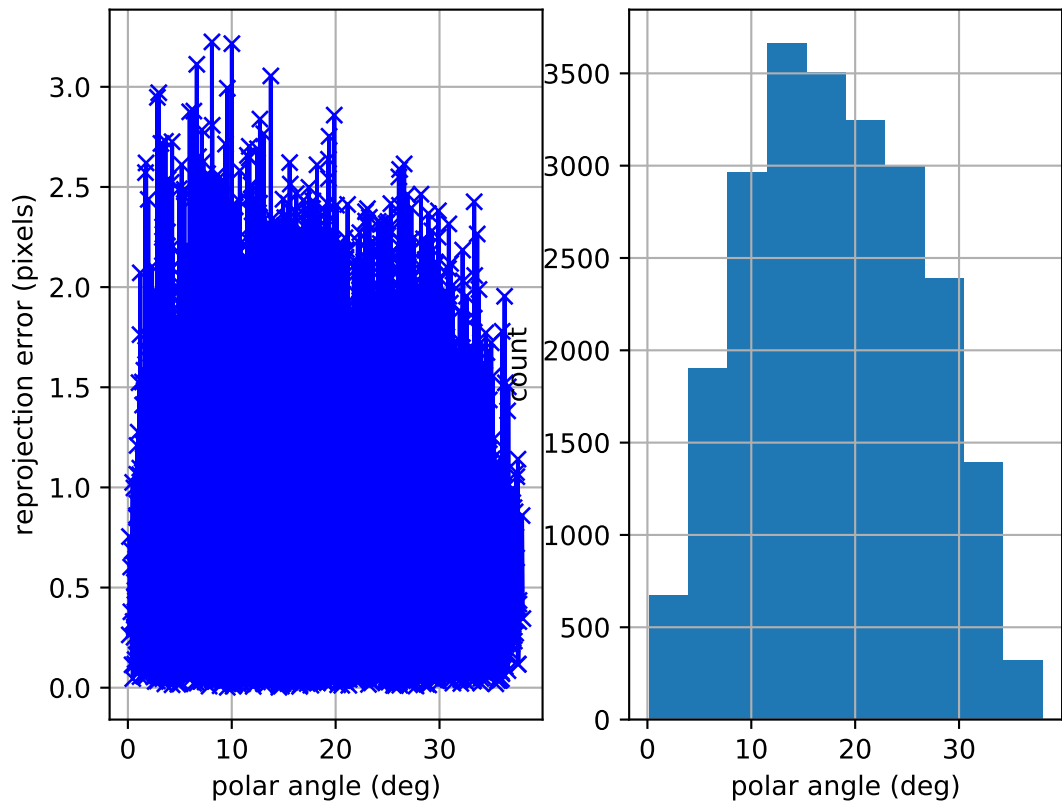
cam1: azimuthal error



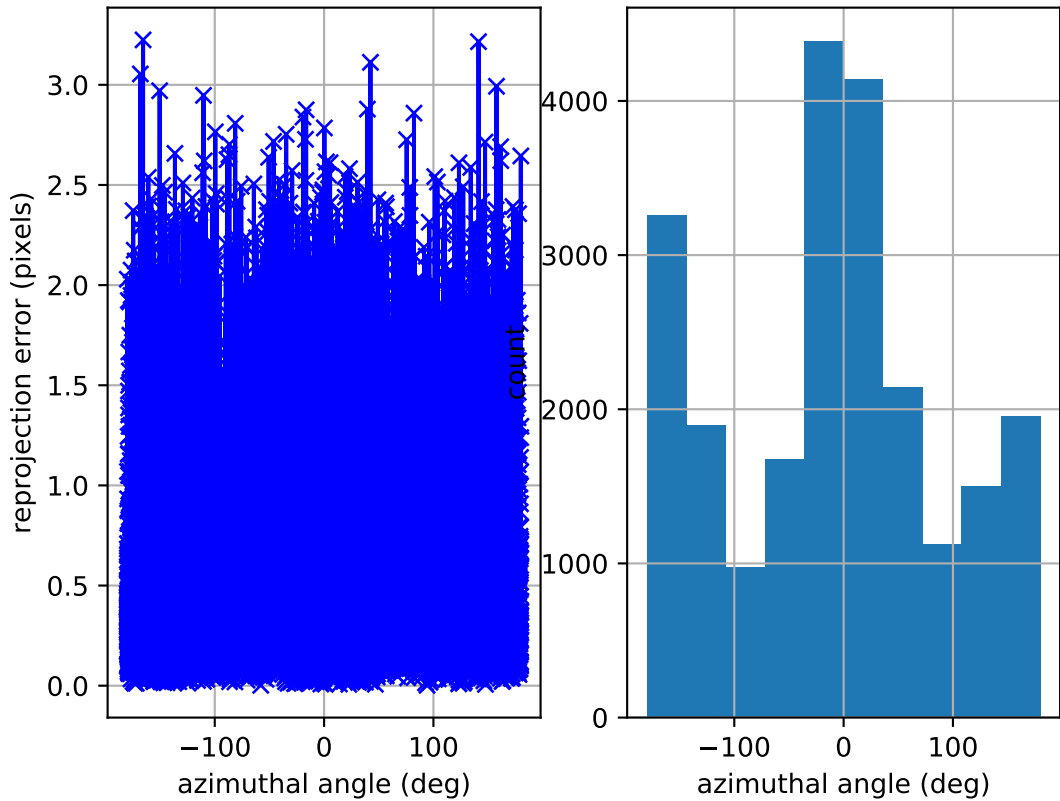
# cam1: reprojection errors



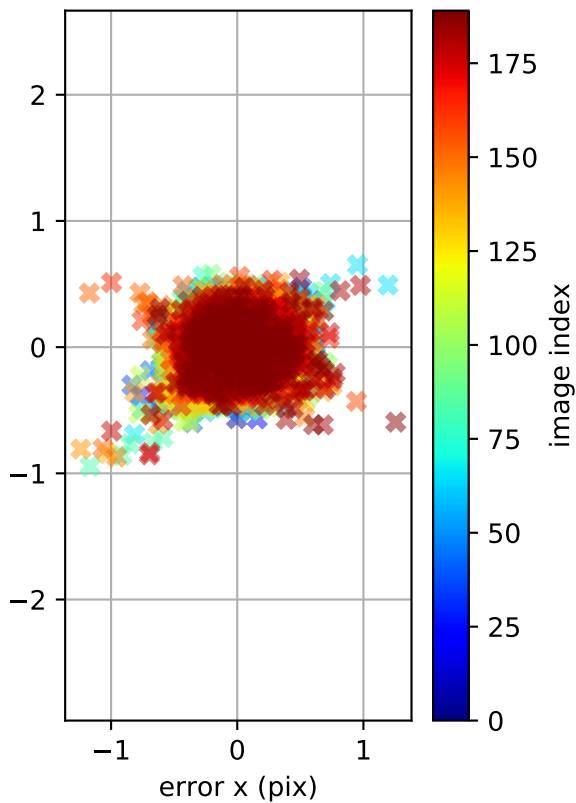
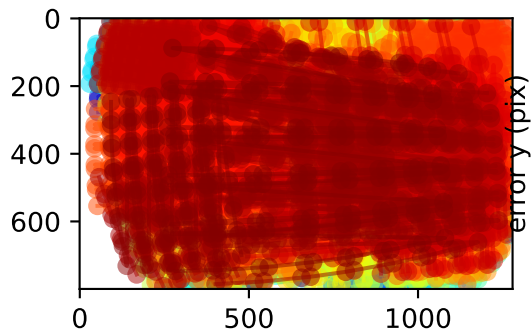
cam2: polar error



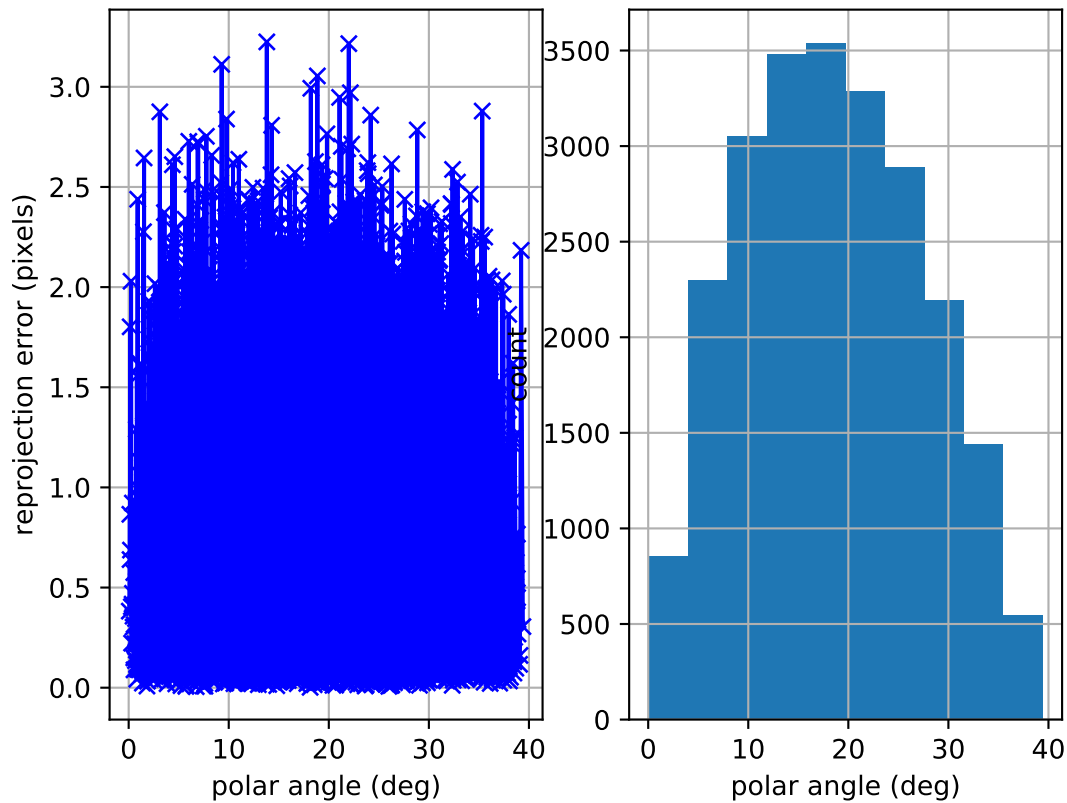
cam2: azimuthal error



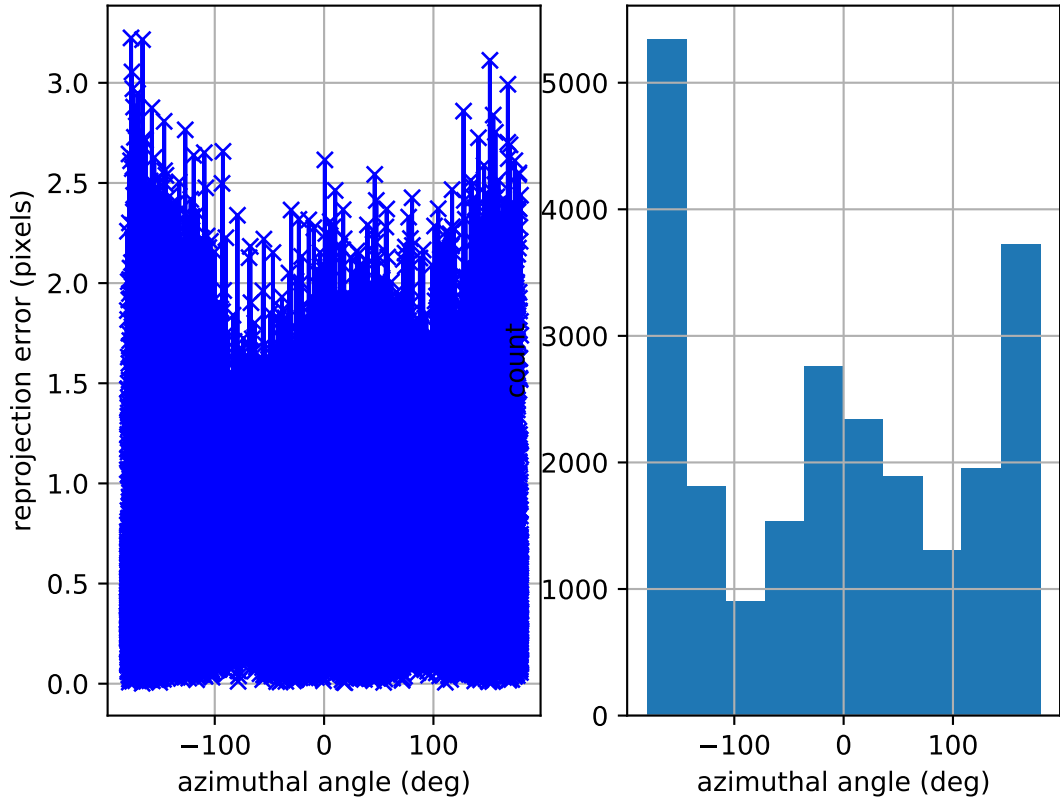
## cam2: reprojection errors



cam3: polar error

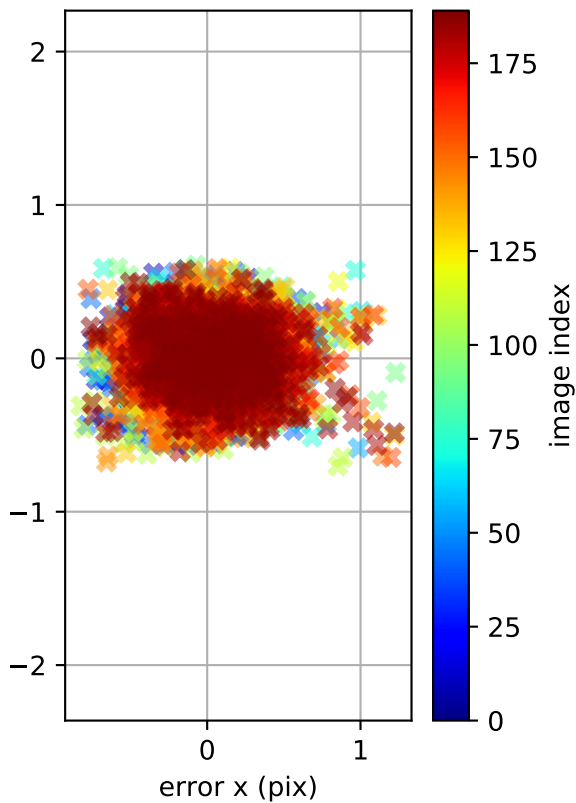
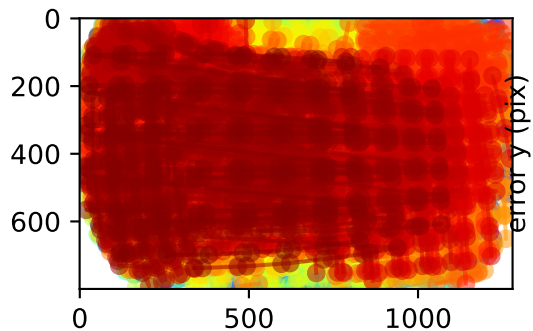


cam3: azimuthal error

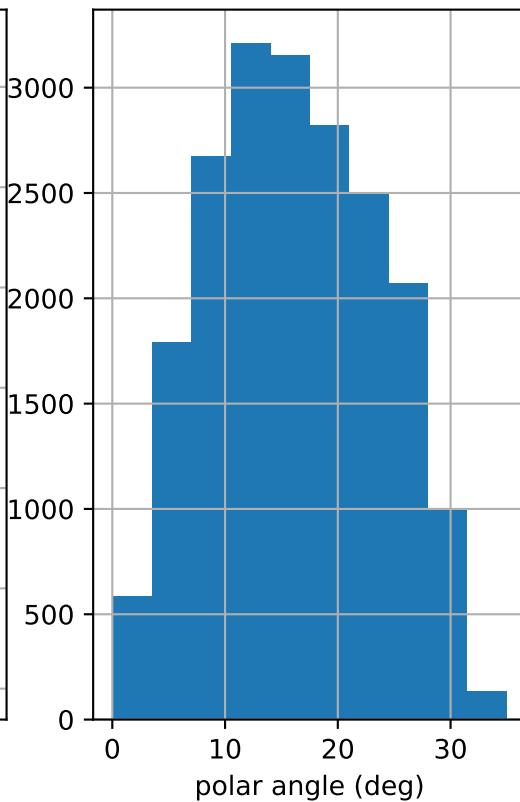
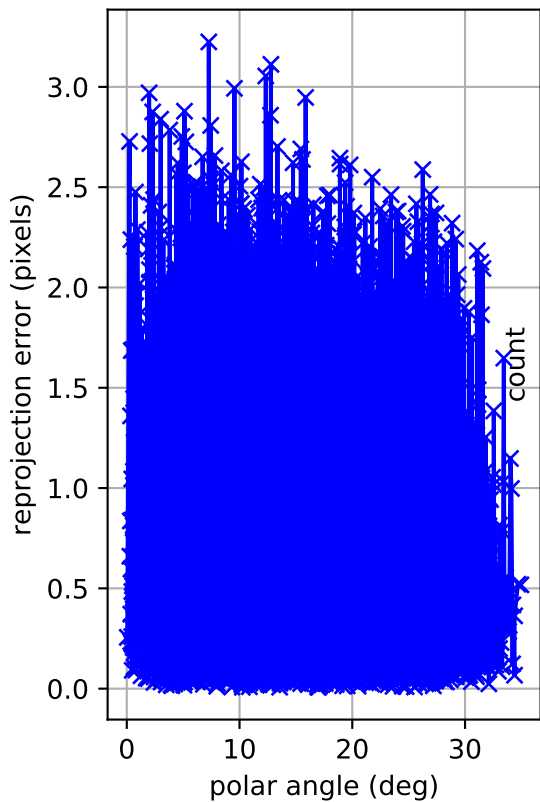




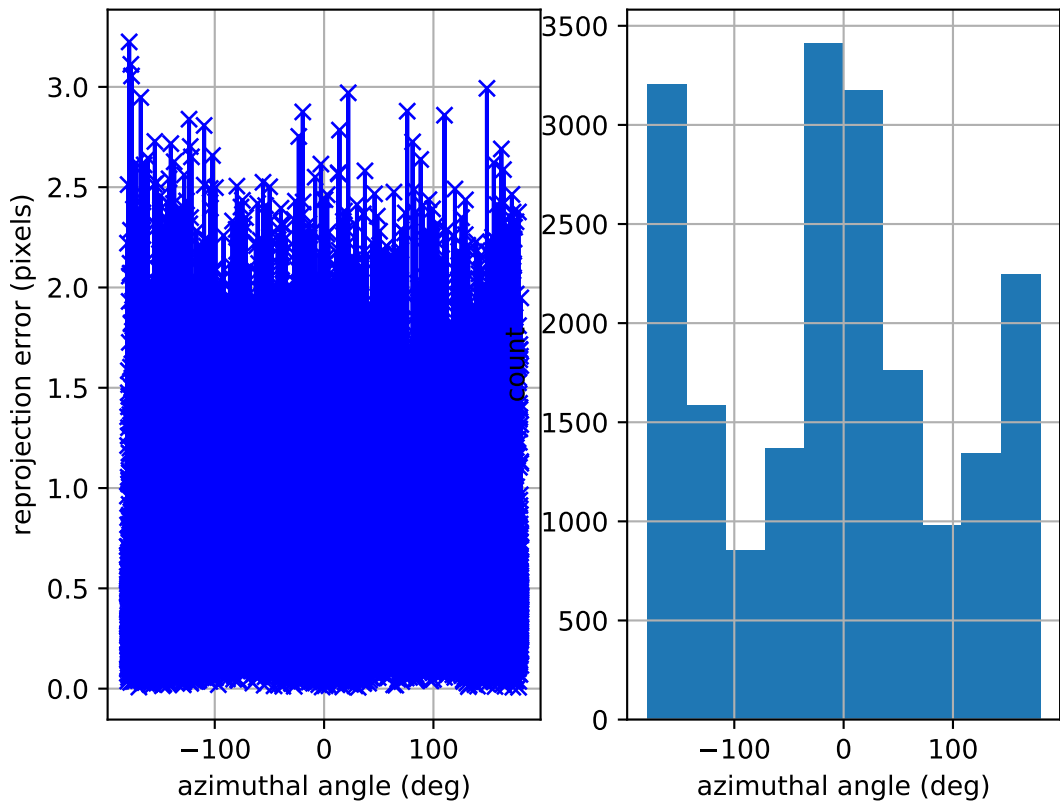
# cam3: reprojection errors



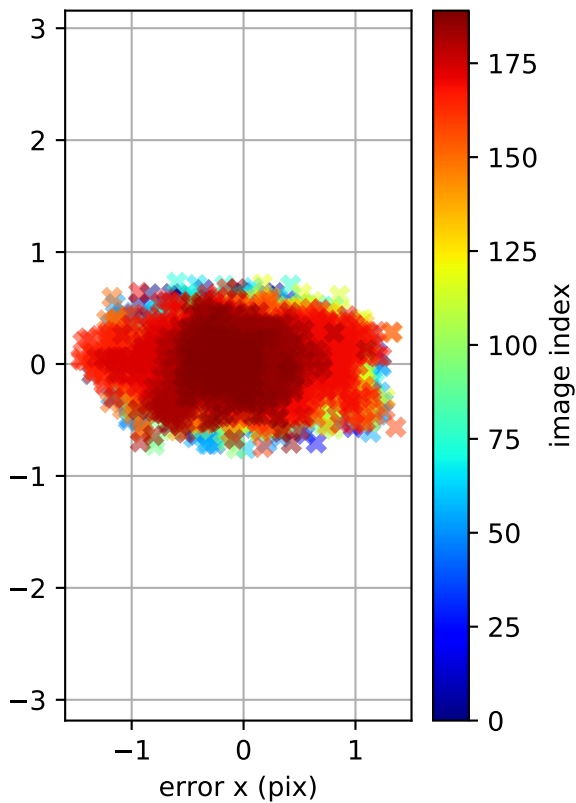
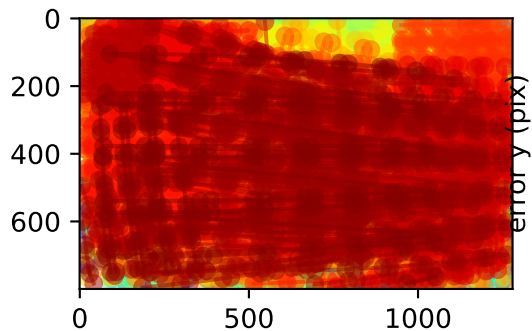
cam4: polar error



cam4: azimuthal error



# cam4: reprojection errors



# Location of removed outlier corners

