

## Calibration results

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### Camera-system parameters:

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

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

distortion: [-0.04715779 0.08369893 0.00067874 -0.00013027] +- [0.00093982 0.00205769 0.00008394 0.00004998]  
projection: [1032.45502044 1032.51758469 637.97674555 367.44439767] +- [0.17011852 0.16827761 0.04013813 0.22292217]

reprojection error: [-0.000003, -0.000022] +- [0.561306, 0.381771]

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

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

distortion: [-0.05077504 0.08001786 0.00182147 0.00045665] +- [0.00091723 0.00196594 0.00007782 0.00005433]  
projection: [1031.29967615 1031.70389847 637.36686421 369.03335374] +- [0.05872856 0.06081084 0.01584583 0.15224075]

reprojection error: [0.000106, -0.000079] +- [0.608002, 0.522573]

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

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

distortion: [-0.39431434 0.15905186 -0.00045513 0.00089647] +- [0.00050098 0.00086151 0.00005213 0.00003162]  
projection: [1058.56121739 1058.71064356 671.59084181 338.93918176] +- [0.15745646 0.15927355 0.03546591 0.20416556]

reprojection error: [0.000261, -0.000338] +- [0.190288, 0.150877]

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

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

distortion: [-0.39194837 0.15254771 -0.0005825 0.00143795] +- [0.0004406 0.00066992 0.00005088 0.0000339 ]  
projection: [1052.72586467 1053.51619252 668.92643155 331.34476774] +- [0.16988547 0.16635048 0.0309507 0.19701978]

reprojection error: [0.000403, -0.000369] +- [0.201592, 0.149885]

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

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

distortion: [-0.41769851 0.19250191 -0.00009369 0.0004298 ] +- [0.00072093 0.00174137 0.00005264 0.00003483]  
projection: [1265.47099506 1265.14659309 648.3423476 369.04241735] +- [0.1483887 0.15123053 0.02068609 0.1212228 ]

reprojection error: [0.000347, -0.000095] +- [0.434431, 0.191469]

#### baseline T\_1\_0:

q: [-0.00103938 0.00117976 -0.0003782 0.99999869] +- [0.00031602 0.00008595 0.00003879]

t: [-0.12019643 0.00090712 -0.00039471] +- [0.0000462 0.00004418 0.00011422]

baseline T\_2\_1:

q: [-0.00108086 -0.00462186 -0.00500124 0.99997623] +- [0.00028163 0.00007775 0.00003643]

t: [0.12011601 0.06933981 0.0042437 ] +- [0.00004414 0.00004205 0.0001147 ]

baseline T\_3\_2:

q: [ 0.00038782 -0.00277396 0.00015608 0.99999607] +- [0.00028041 0.00007748 0.00003207]

t: [-0.11996923 -0.00013904 0.00105266] +- [0.00004329 0.00003949 0.0001496 ]

baseline T\_4\_3:

q: [0.00251186 0.0048876 0.00052346 0.99998476] +- [0.00024288 0.0000672 0.00003195]

t: [0.08869039 0.00625874 0.00329731] +- [0.00004074 0.00003566 0.00013882]

Target configuration

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Type: aprilgrid

Tags:

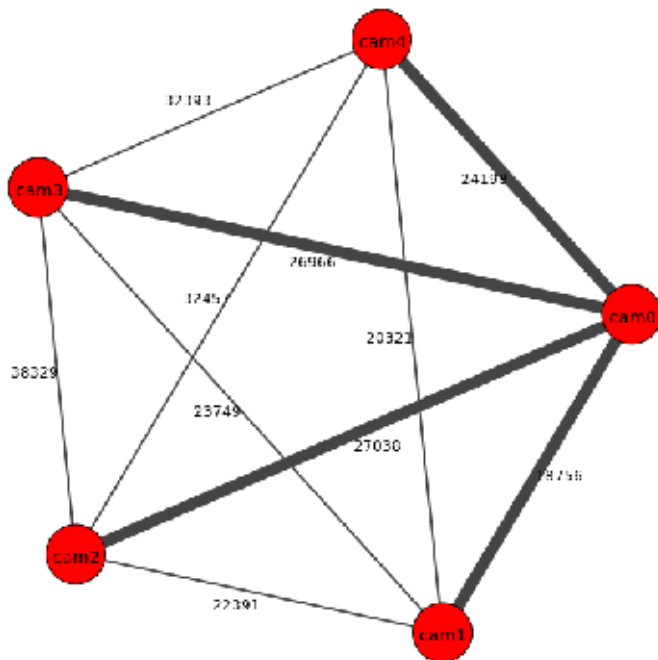
Rows: 5

Cols: 7

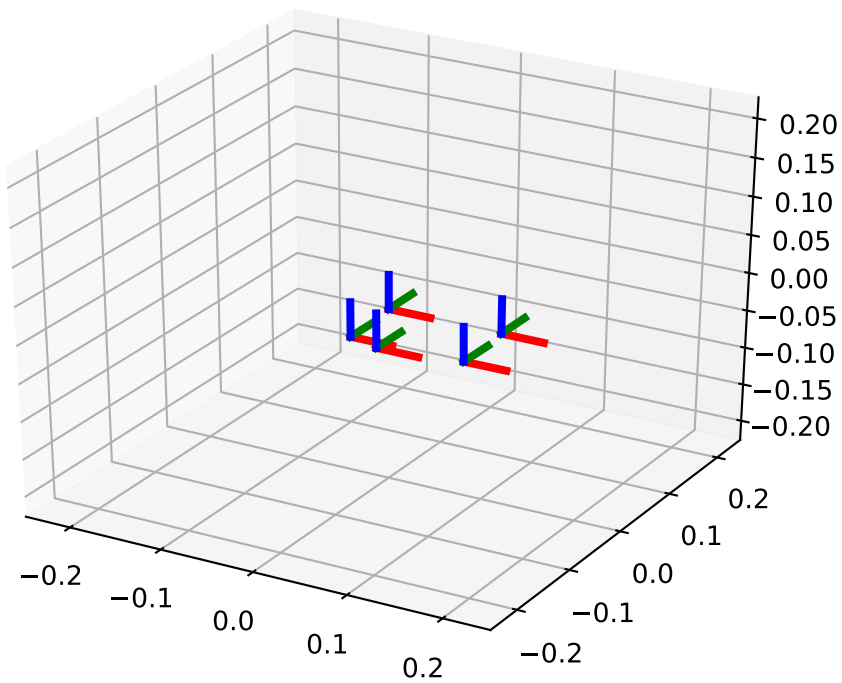
Size: 0.04 [m]

Spacing 0.01 [m]

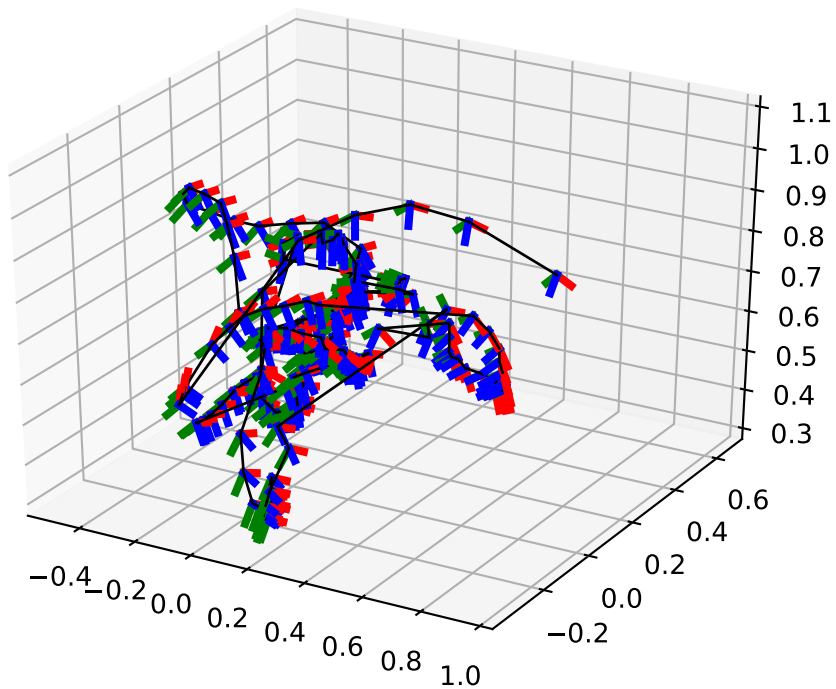
# Inter-camera observations graph (edge weight=#mutual obs.)



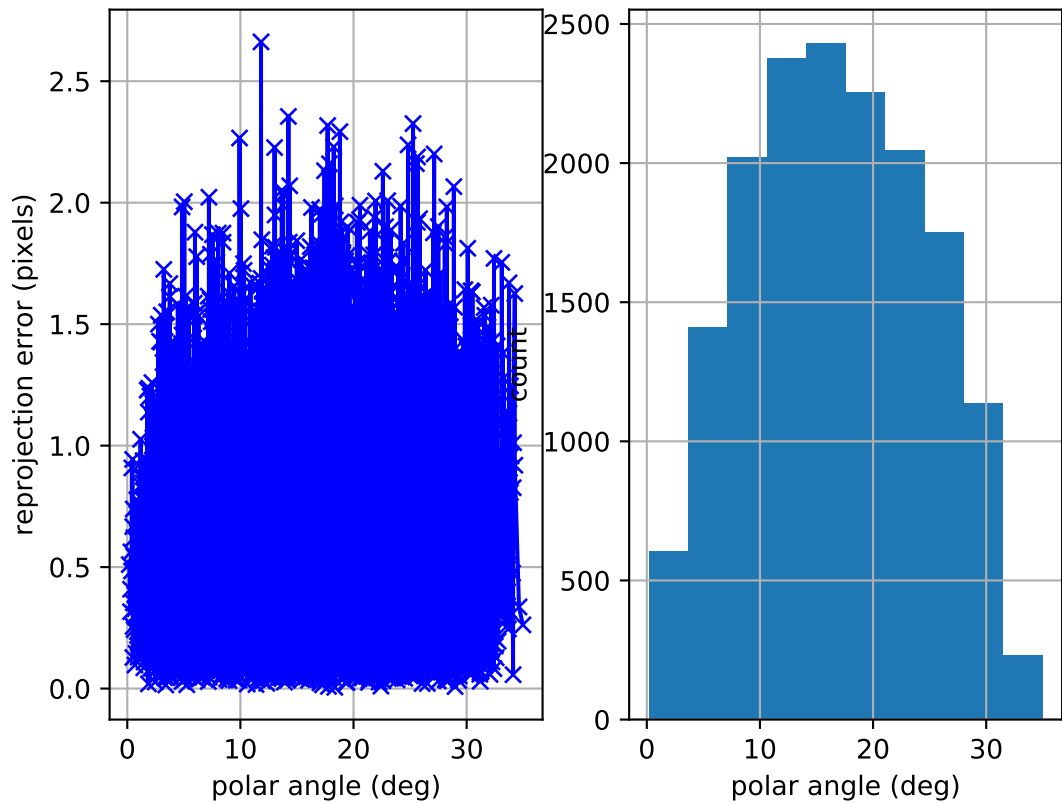
camera system



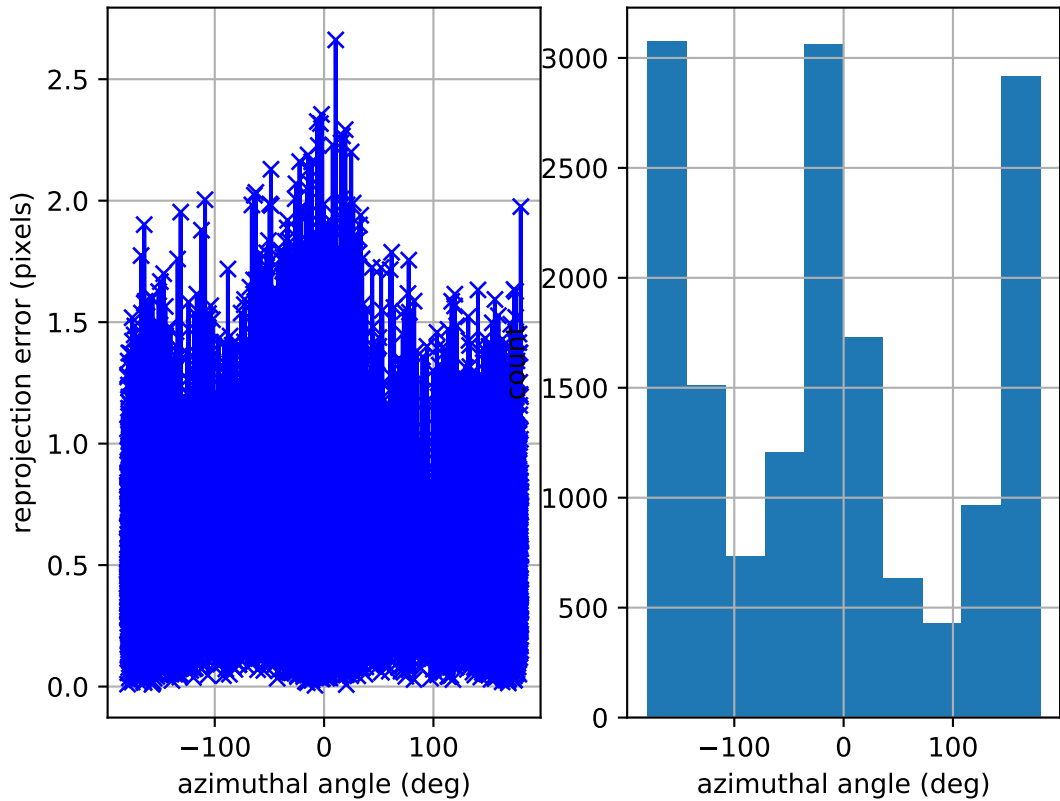
cam0: estimated poses



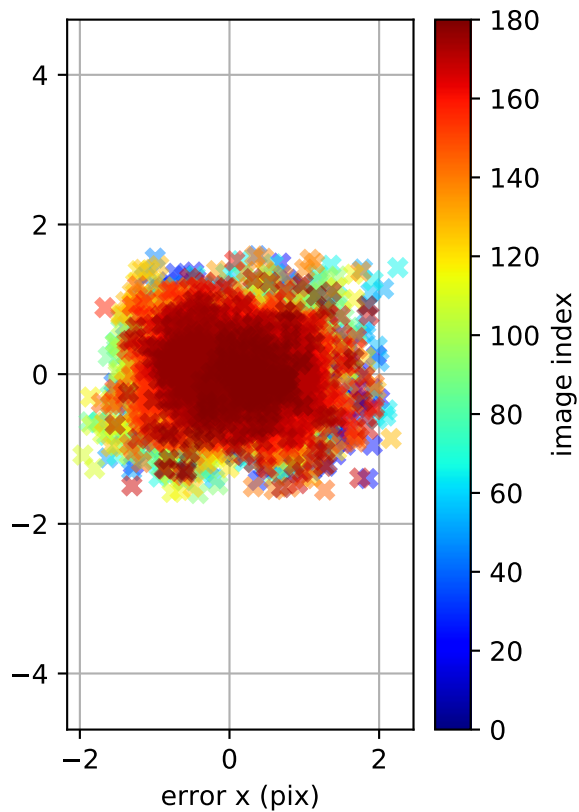
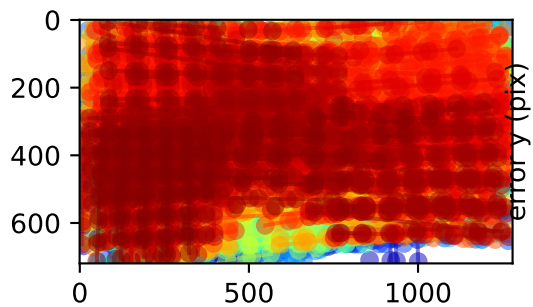
cam0: polar error



cam0: azimuthal error

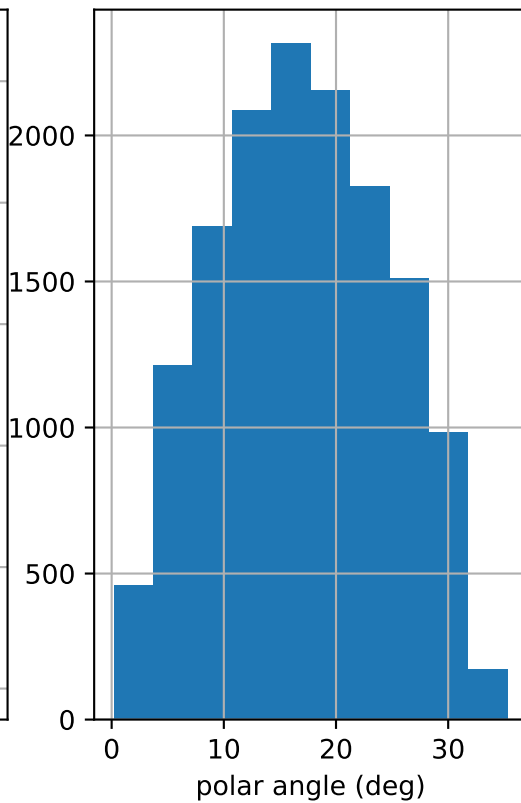
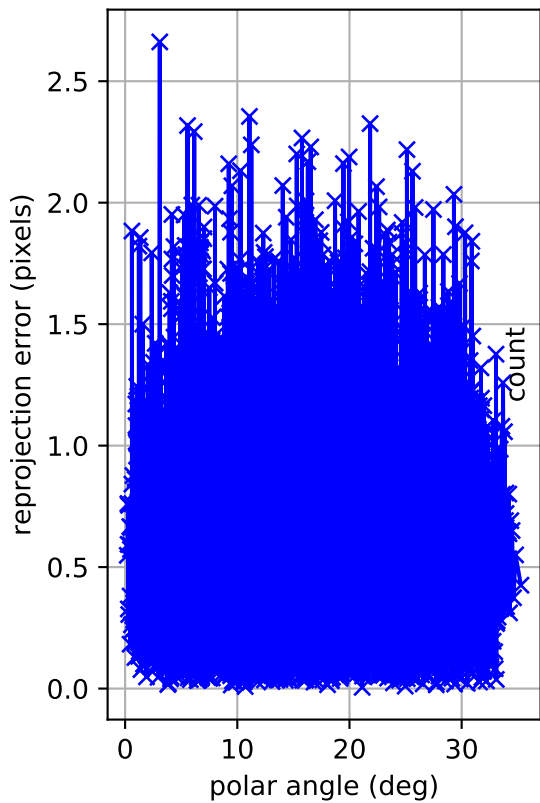


# cam0: reprojection errors

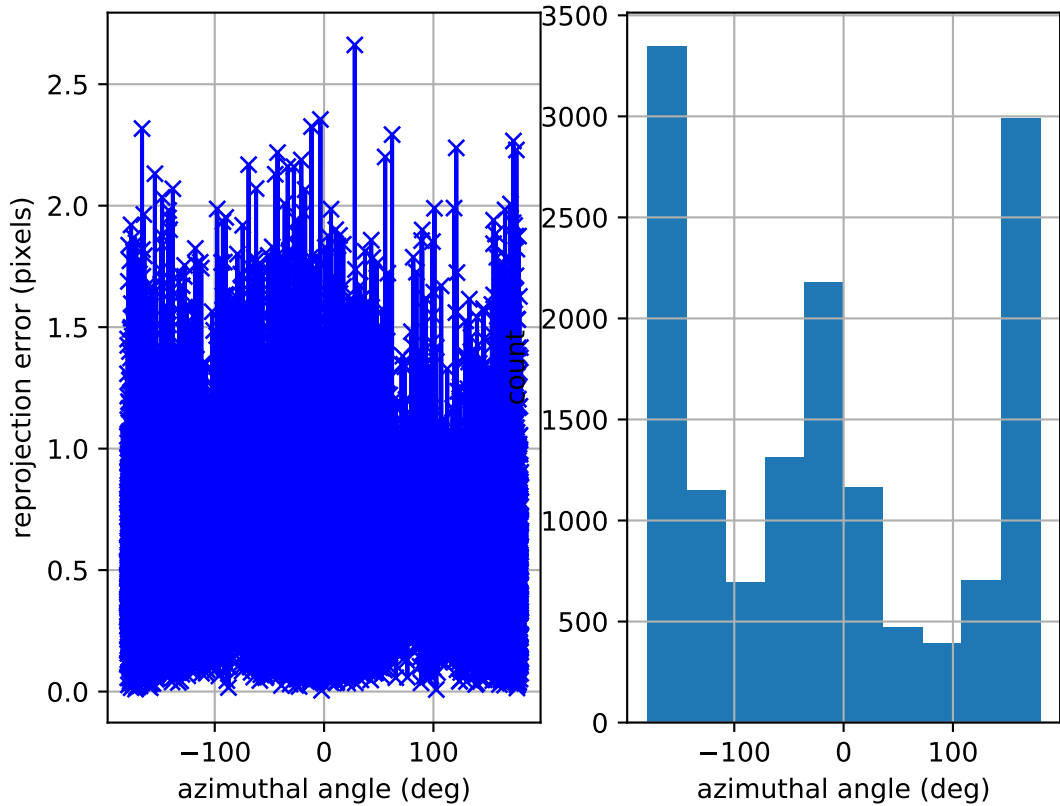




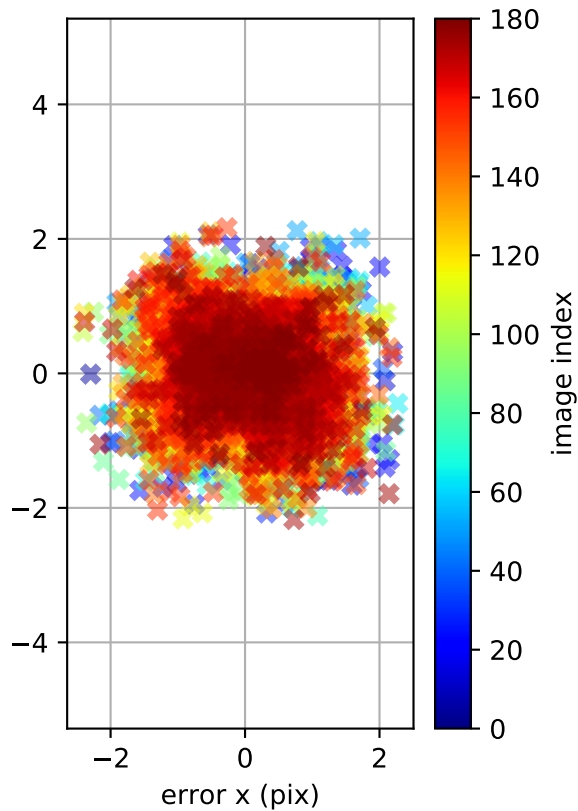
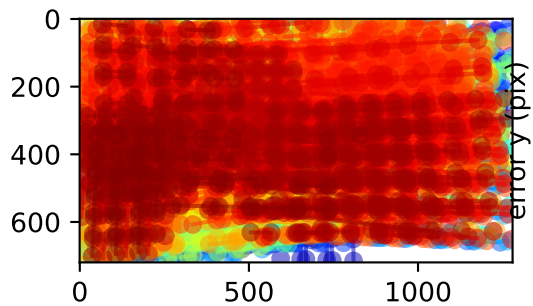
cam1: polar error



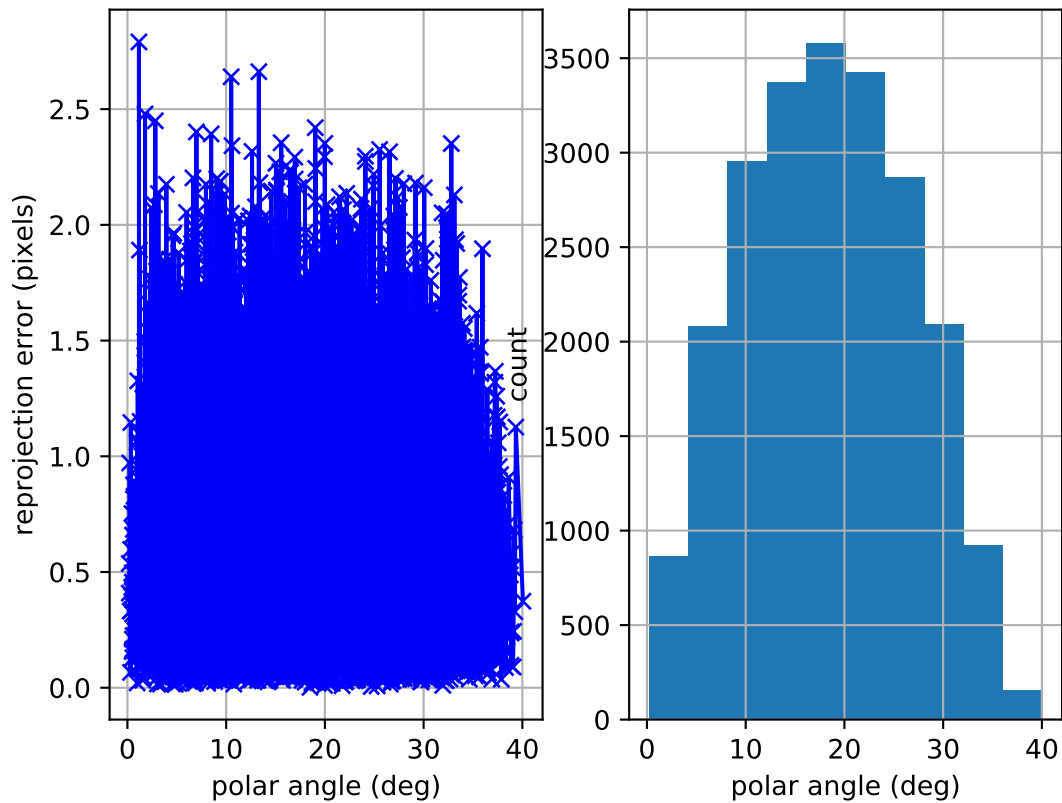
cam1: azimuthal error



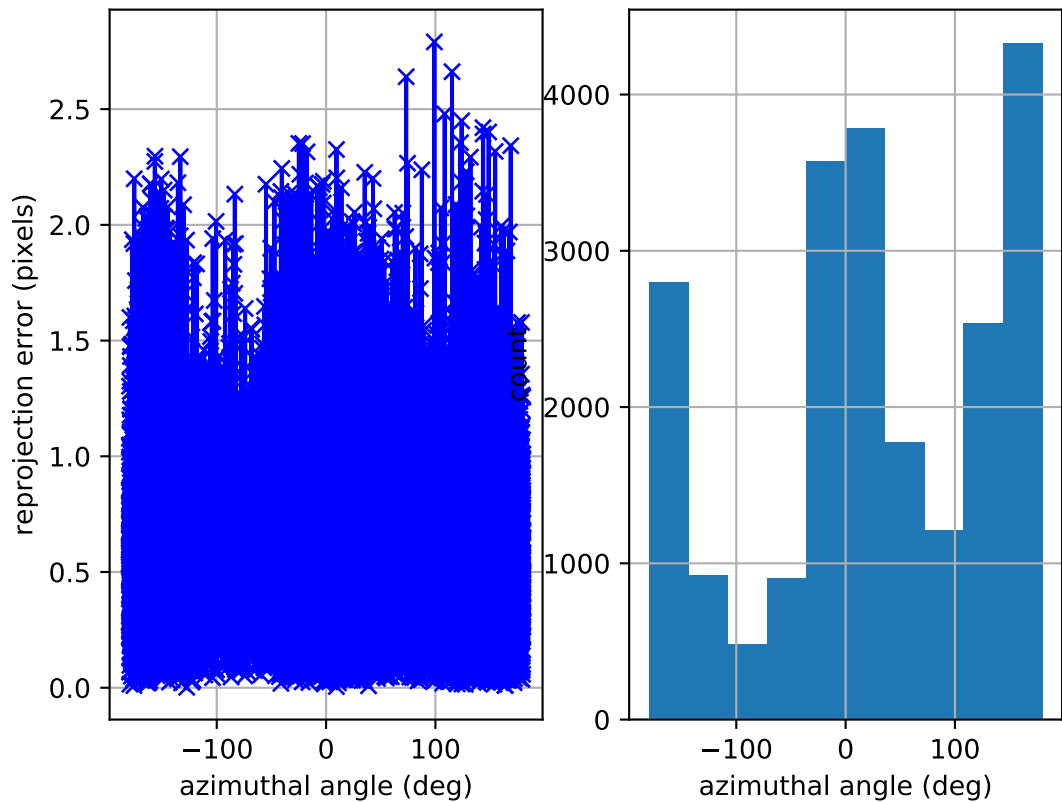
# cam1: reprojection errors



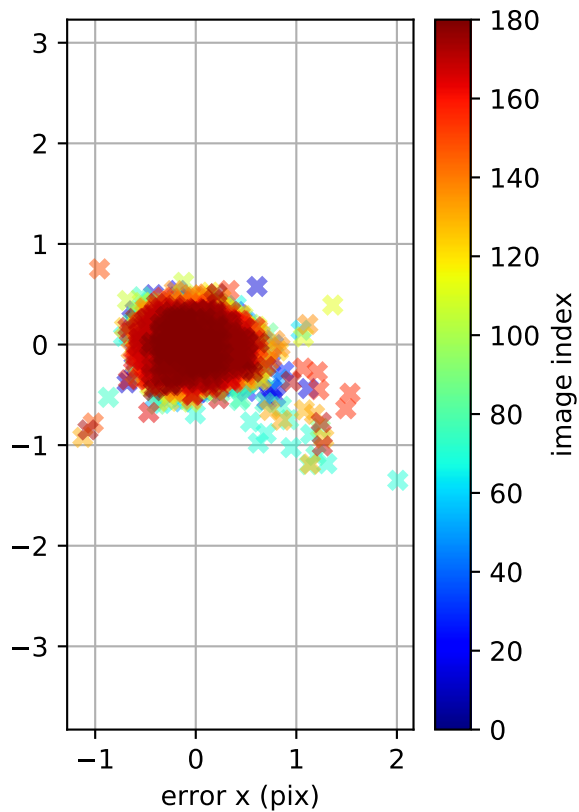
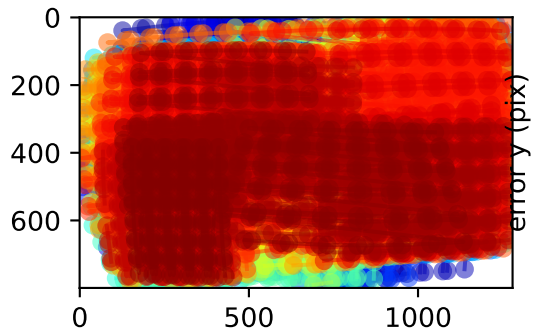
cam2: polar error



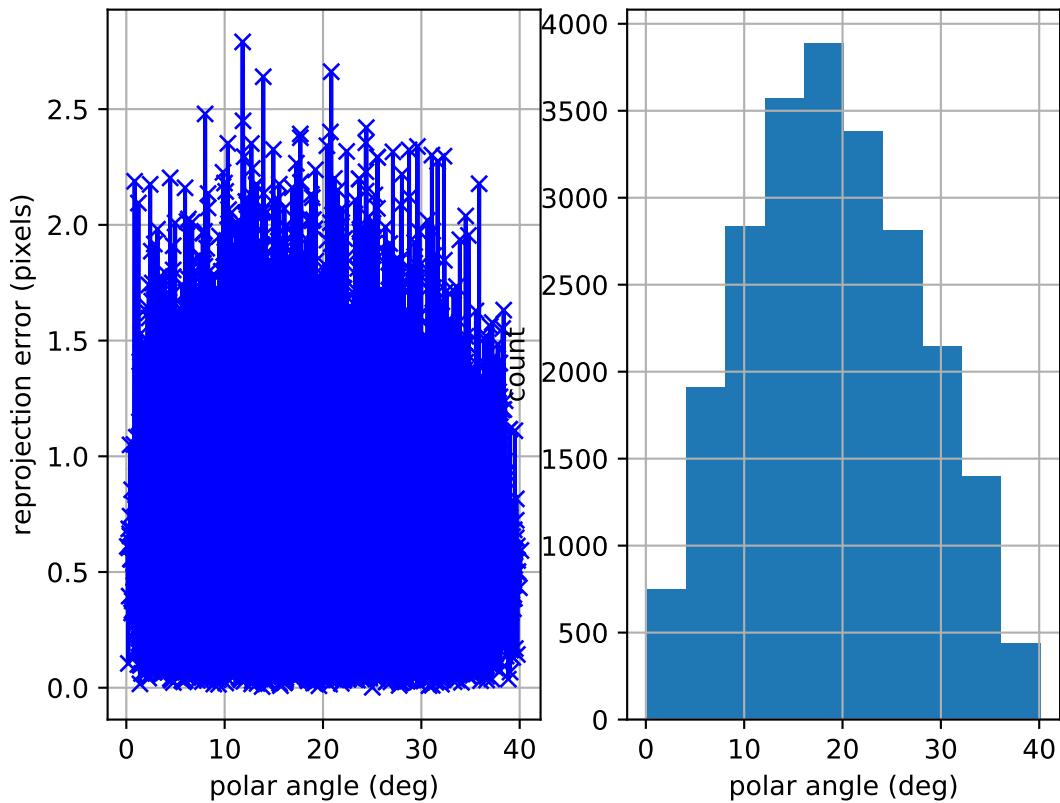
cam2: azimuthal error



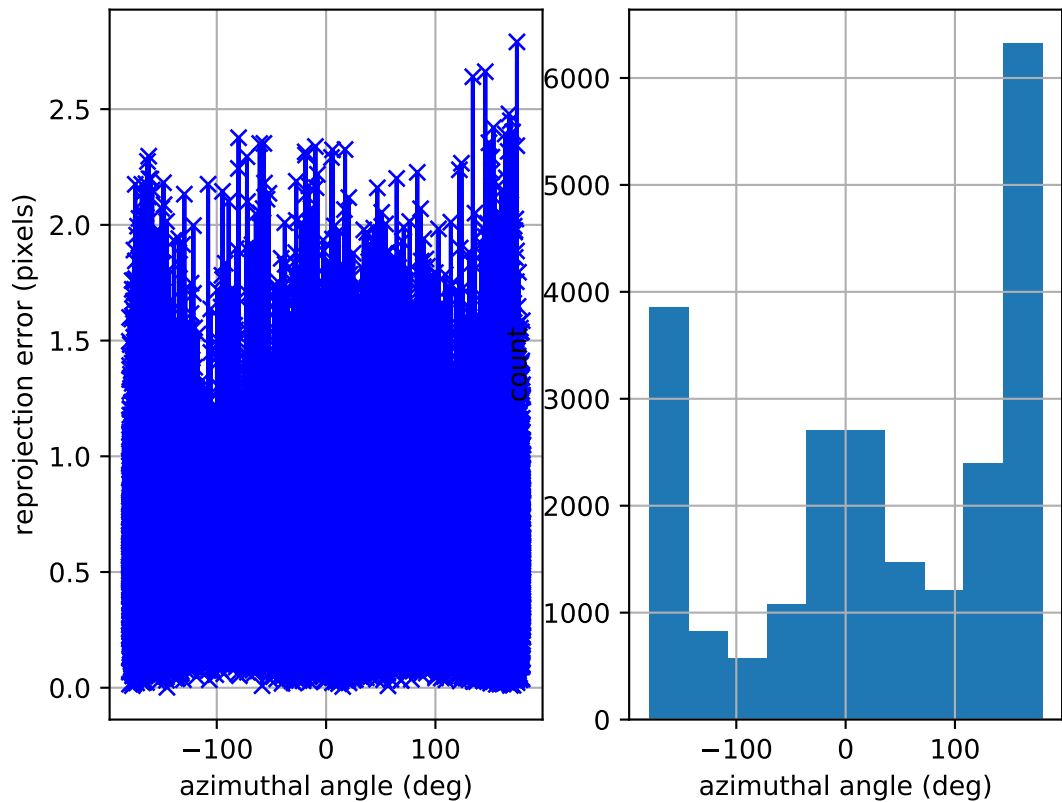
# cam2: reprojection errors



cam3: polar error

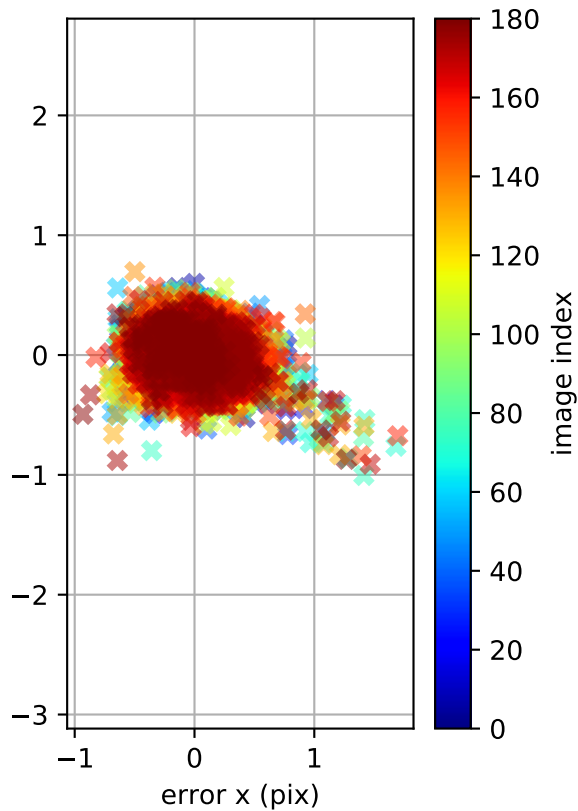
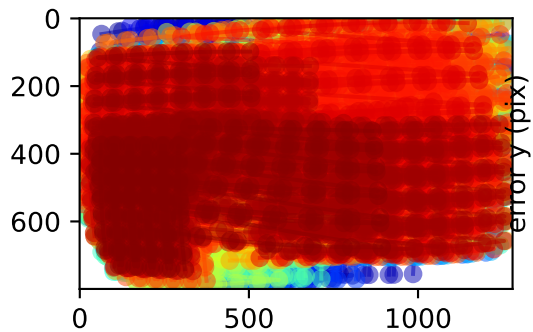


cam3: azimuthal error

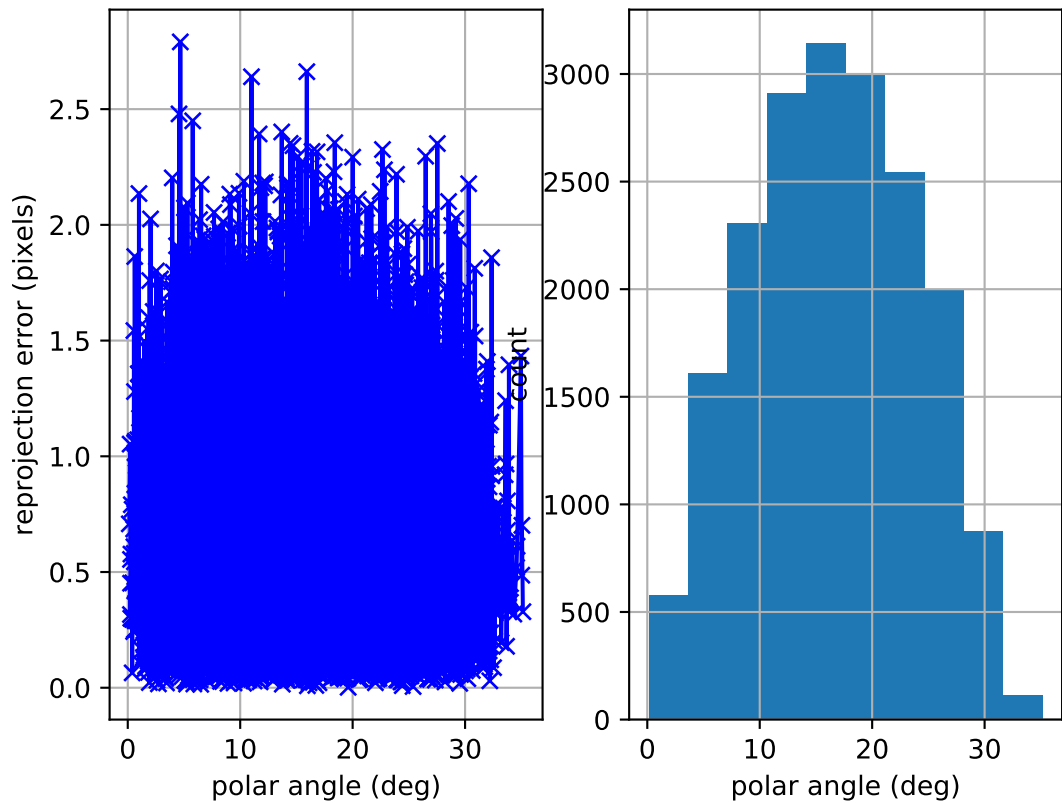




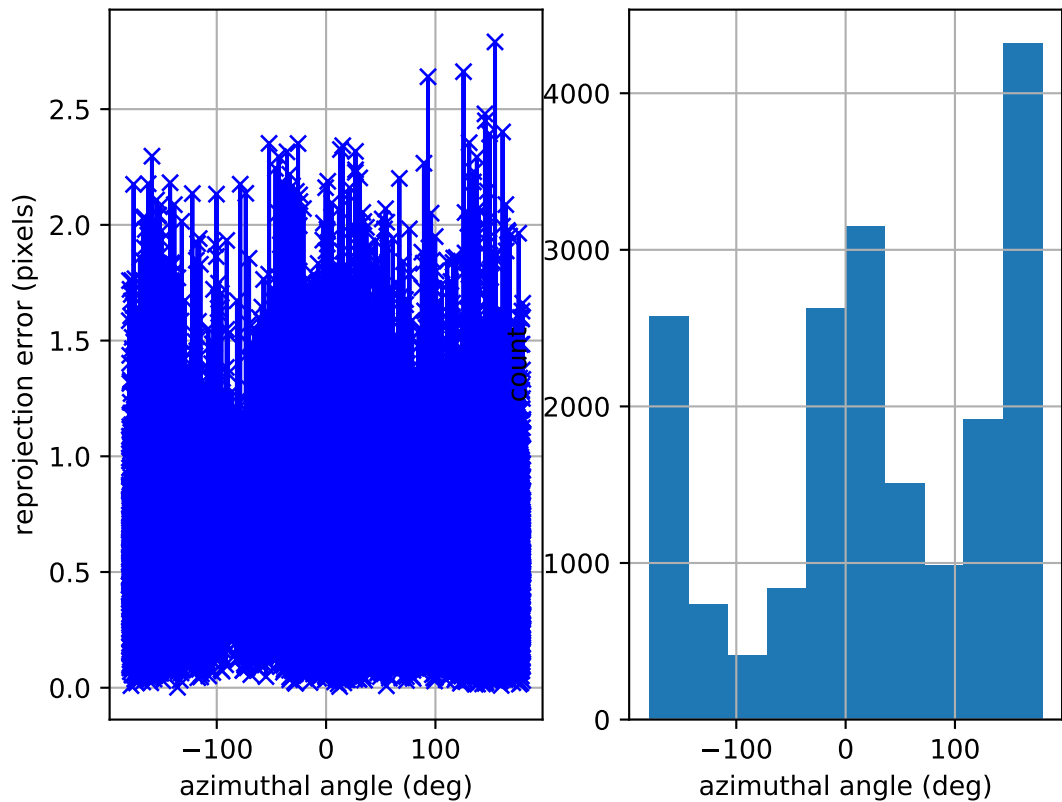
# cam3: reprojection errors



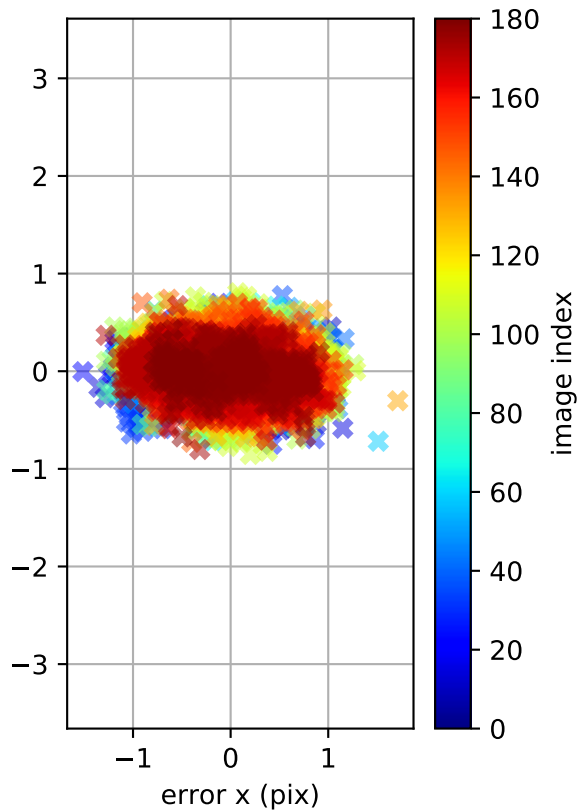
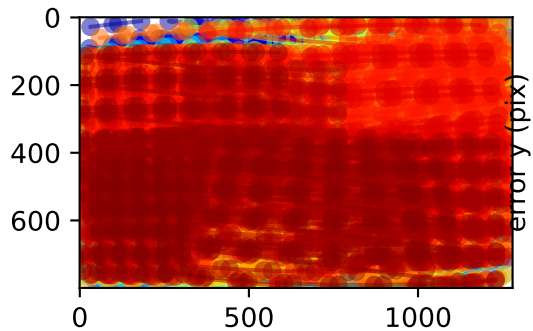
cam4: polar error



cam4: azimuthal error



# cam4: reprojection errors



# Location of removed outlier corners

