

## Calibration results

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### Camera-system parameters:

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

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

distortion: [-0.0468324 0.07737948 0.00140623 0.00010979] +- [0.00088898 0.00192225 0.00006743 0.00004928]

projection: [1034.51174254 1034.4542482 639.04165523 372.18139648] +- [0.11346809 0.11389261 0.00433735 0.11165505]

reprojection error: [0.000263, 0.000011] +- [0.723119, 0.710406]

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

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

distortion: [-0.0484952 0.0723172 0.0027192 0.0008377] +- [0.0008833 0.00190888 0.00006555 0.00005018]

projection: [1034.00133065 1033.95609225 639.64899902 374.11167662] +- [0.12034204 0.12263363 0.00575441 0.07683072]

reprojection error: [0.000280, -0.000109] +- [0.758301, 0.704035]

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

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

distortion: [-0.39364989 0.15657989 -0.00003721 0.00039002] +- [0.00046583 0.0007749 0.00004561 0.00003092]

projection: [1058.99548278 1059.45222349 677.21795654 336.1079182] +- [0.09847296 0.09981661 0.01517068 0.17377538]

reprojection error: [0.000225, -0.000499] +- [0.322600, 0.300042]

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

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

distortion: [-0.39123127 0.148327 -0.00024868 0.00092917] +- [0.00037566 0.00055179 0.00004428 0.00003081]

projection: [1054.8719466 1055.27991126 674.50515947 329.36087998] +- [0.09602681 0.10017766 0.0097391 0.17198218]

reprojection error: [0.000253, -0.000670] +- [0.343710, 0.299494]

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

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

distortion: [-0.4173765 0.18961124 0.00056624 -0.00011323] +- [0.00071314 0.00167479 0.00004808 0.00003385]

projection: [1266.26951577 1266.5868624 653.84225274 364.17219888] +- [0.1146677 0.11353735 0.00140036 0.04040129]

reprojection error: [-0.000006, 0.000153] +- [0.415644, 0.406135]

#### baseline T\_1\_0:

q: [-0.00134526 0.00164791 -0.00050355 0.99999761] +- [0.00007181 0.00004812 0.00003347]

t: [-0.12025872 0.00101944 -0.00015268] +- [0.00002672 0.00002435 0.00007811]

baseline T\_2\_1:

q: [ 0.00289736 -0.00299434 -0.00528548 0.99997735] +- [0.00021163 0.00004955 0.00003165]

t: [0.12008108 0.06928587 0.00372253] +- [0.00002572 0.00002415 0.00007638]

baseline T\_3\_2:

q: [-0.00006367 -0.00257224 0.00022531 0.99999666] +- [0.0002535 0.00004756 0.0000277 ]

t: [-0.11990936 -0.00010915 0.00124869] +- [0.0000234 0.00002147 0.00006957]

baseline T\_4\_3:

q: [0.00354223 0.00437314 0.00038551 0.99998409] +- [0.00018976 0.00004077 0.00002787]

t: [0.08876606 0.00623615 0.00305912] +- [0.00002293 0.0000211 0.00007015]

Target configuration

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Type: aprilgrid

Tags:

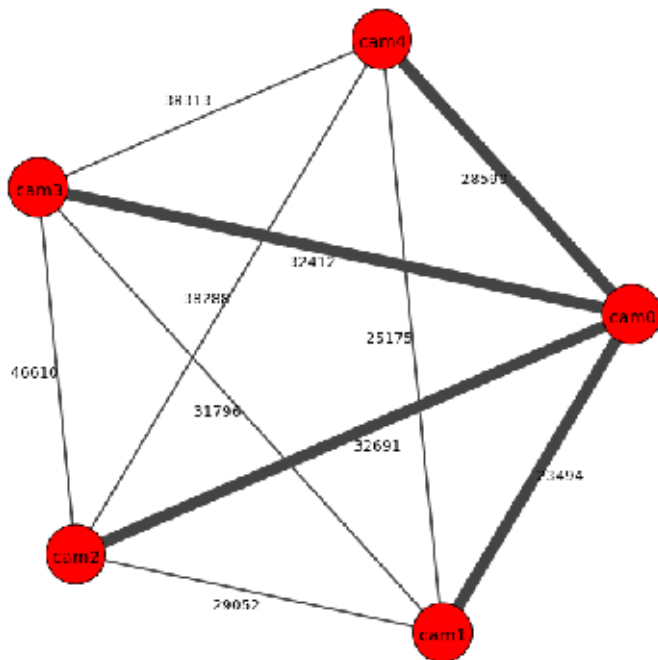
Rows: 5

Cols: 7

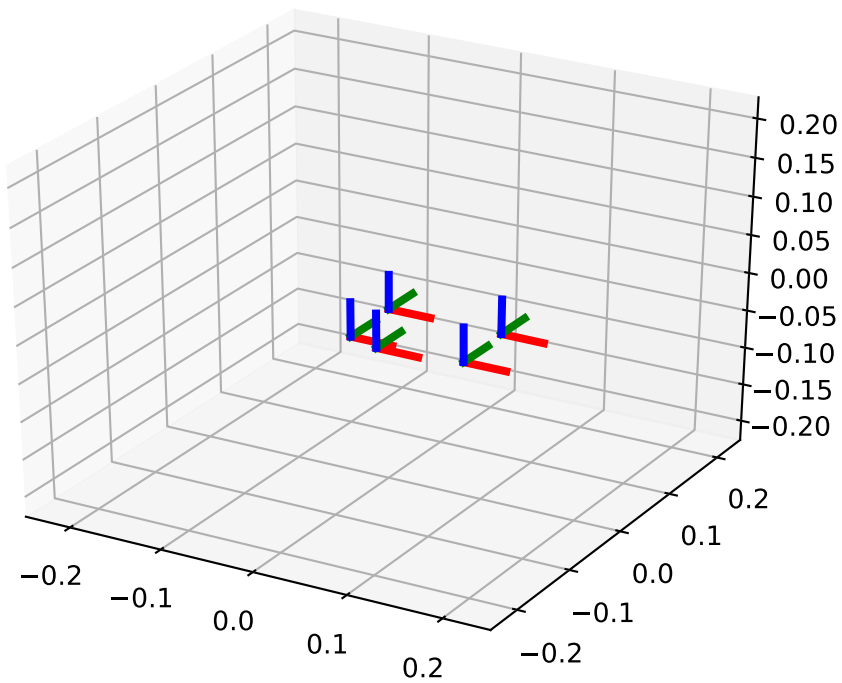
Size: 0.04 [m]

Spacing 0.01 [m]

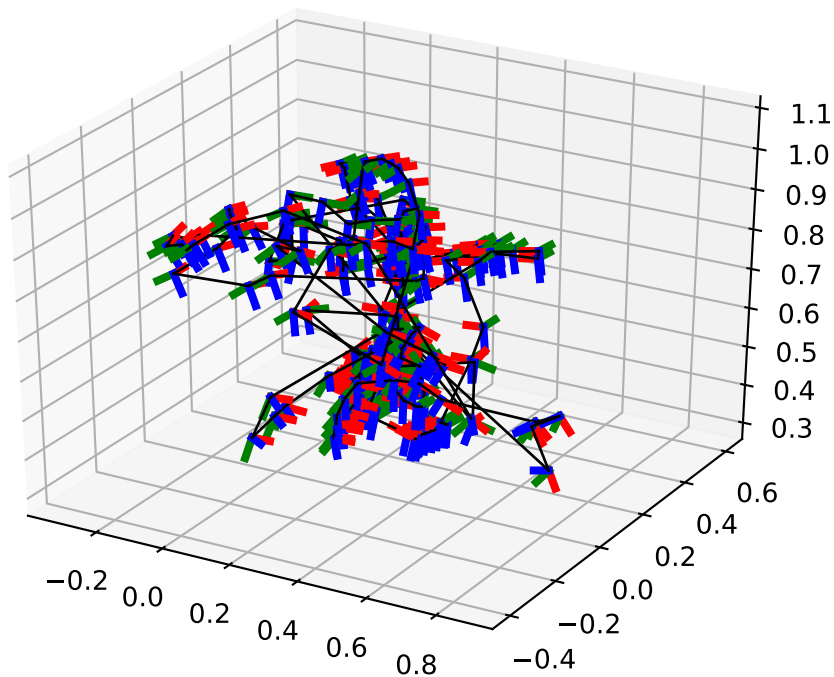
# Inter-camera observations graph (edge weight=#mutual obs.)



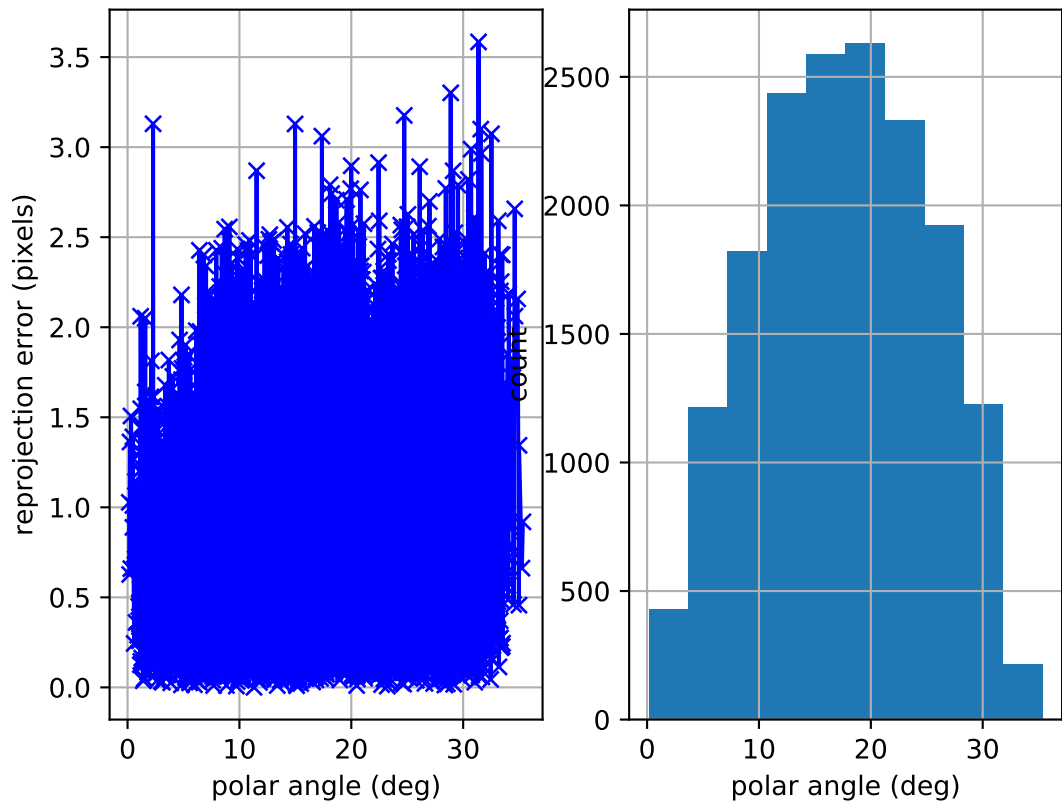
# camera system



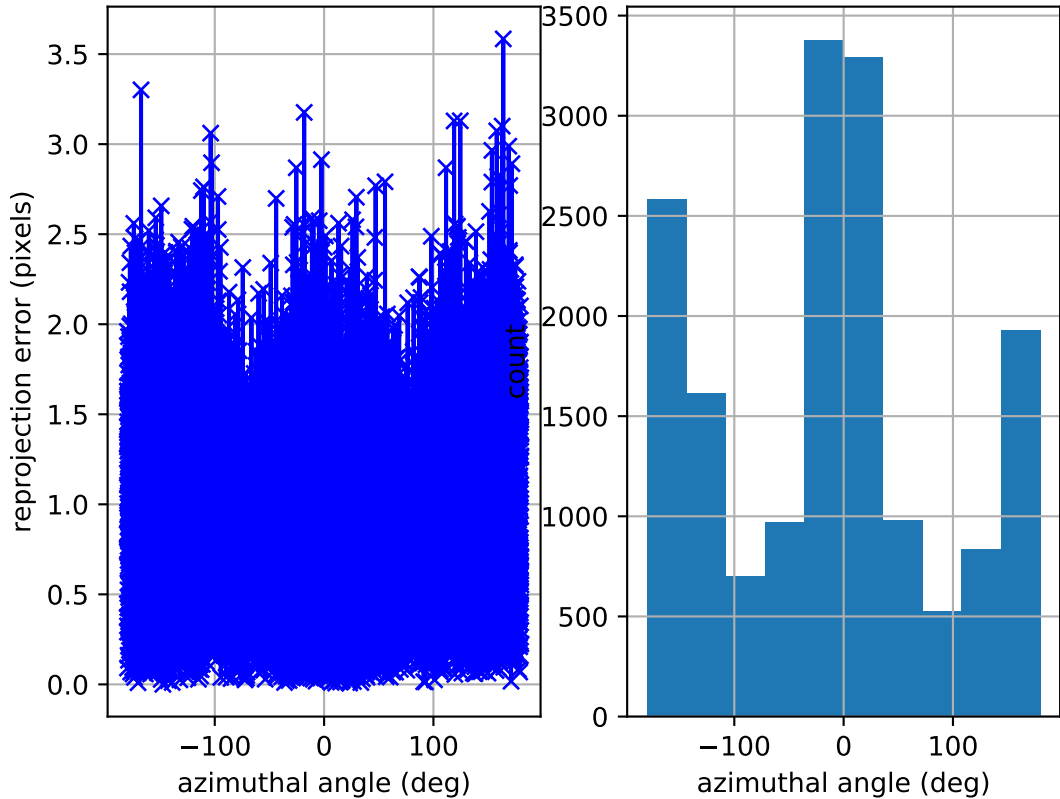
cam0: estimated poses



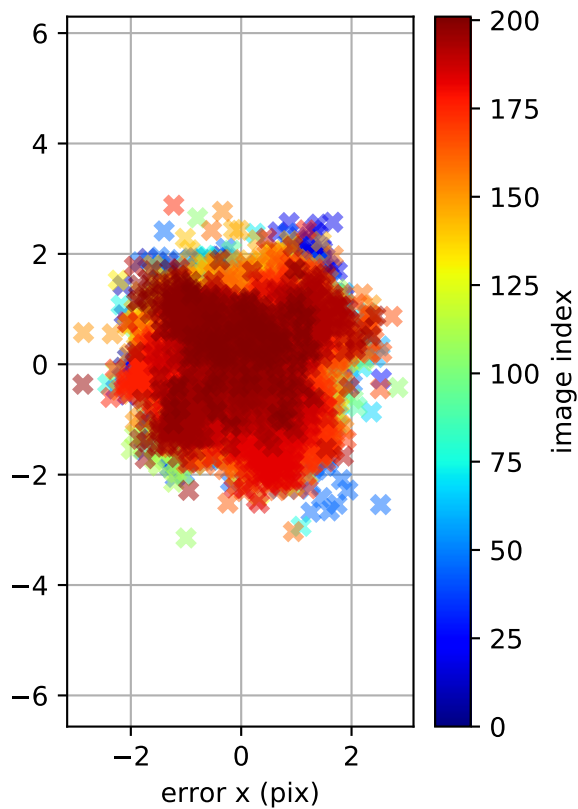
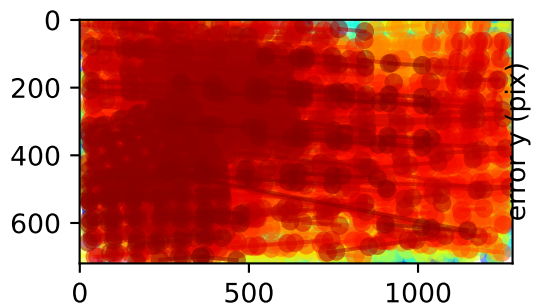
cam0: polar error



cam0: azimuthal error

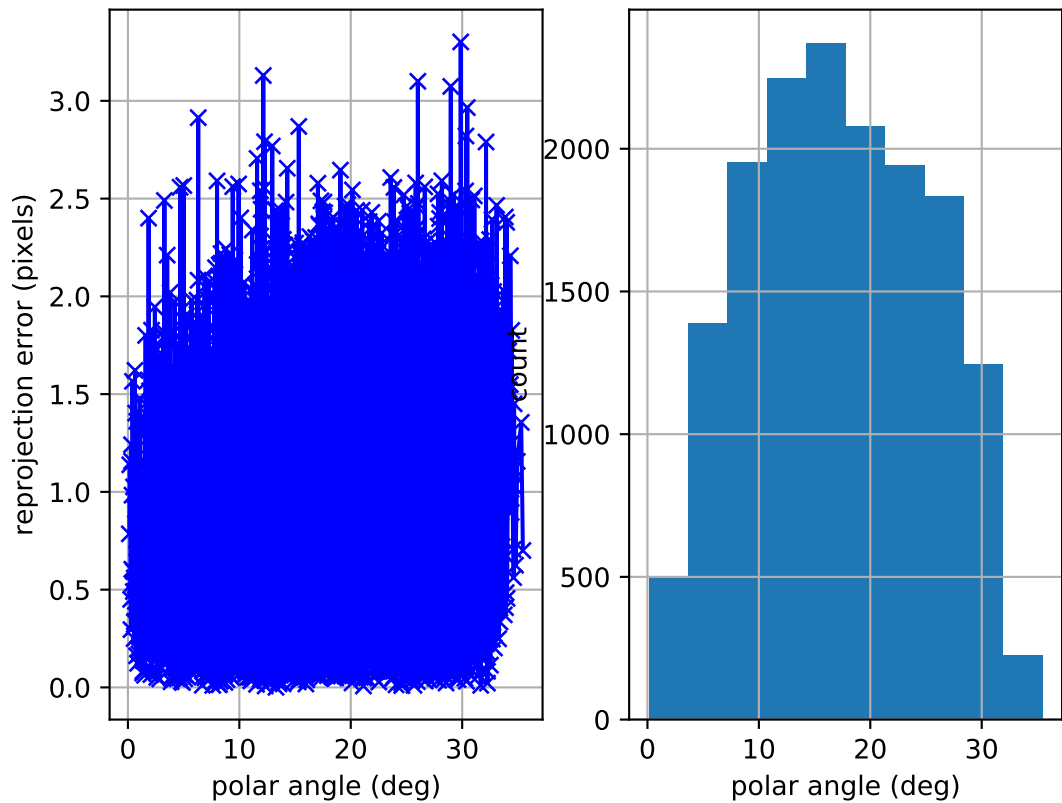


# cam0: reprojection errors

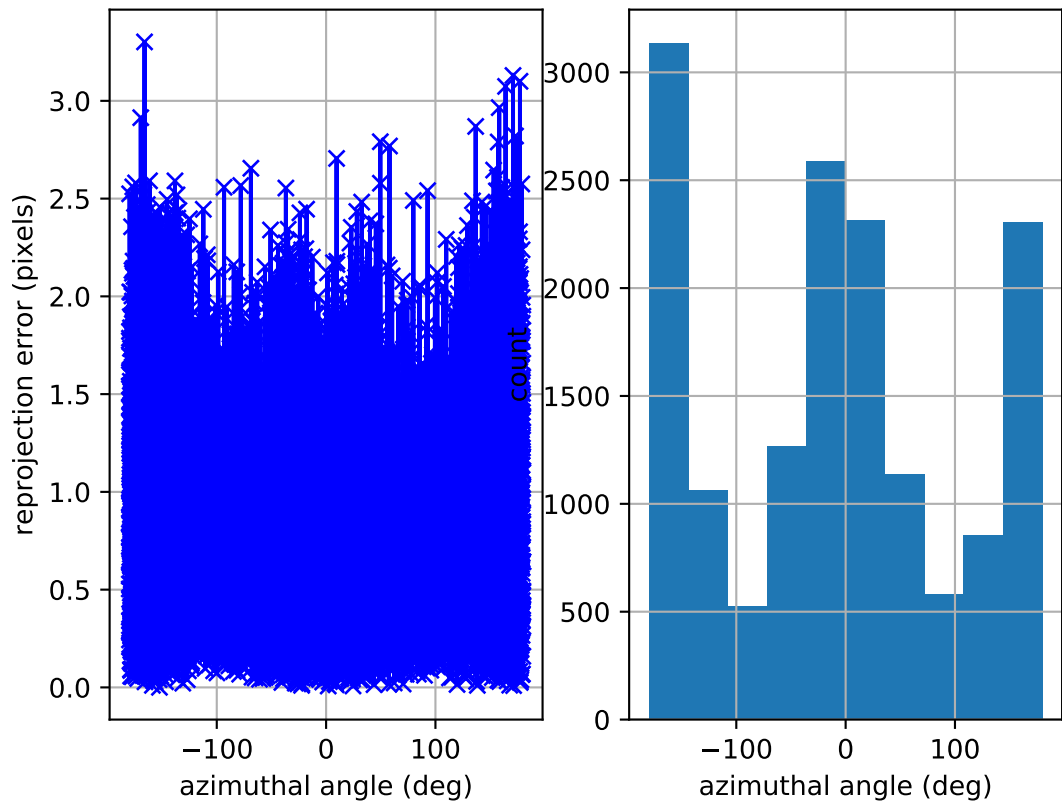




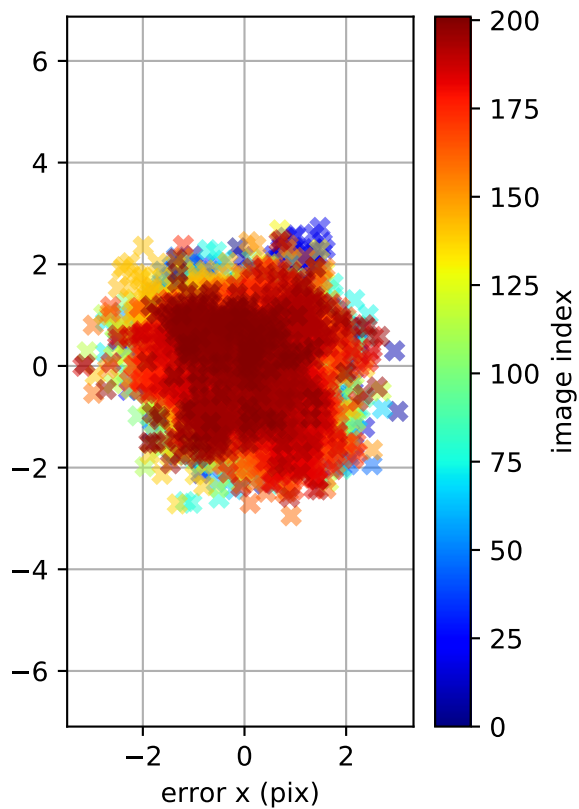
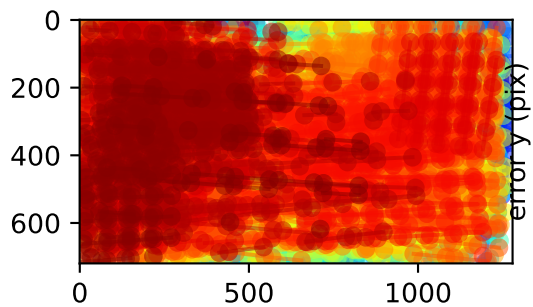
cam1: polar error



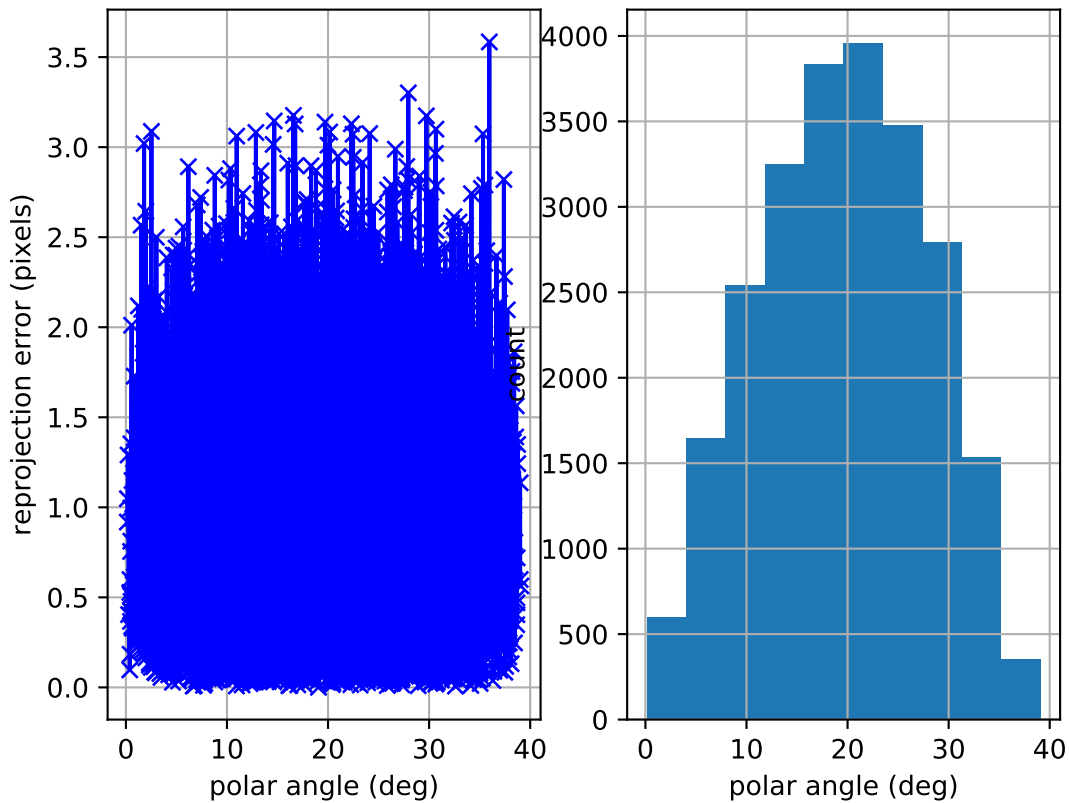
cam1: azimuthal error



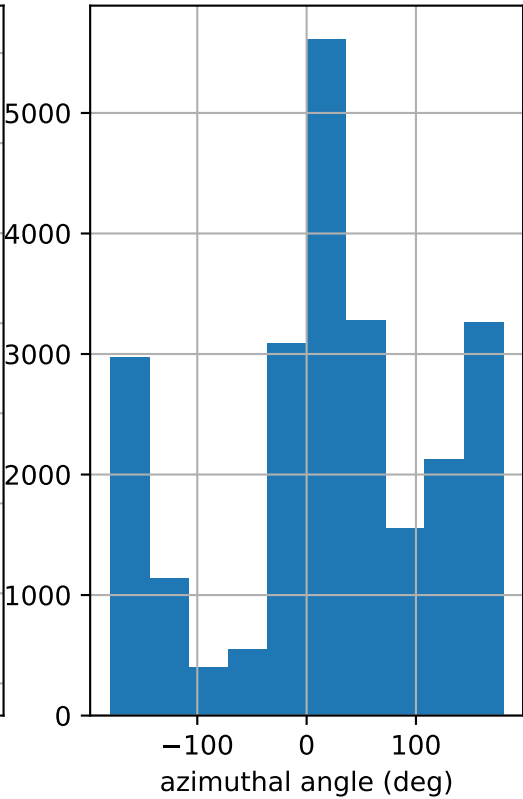
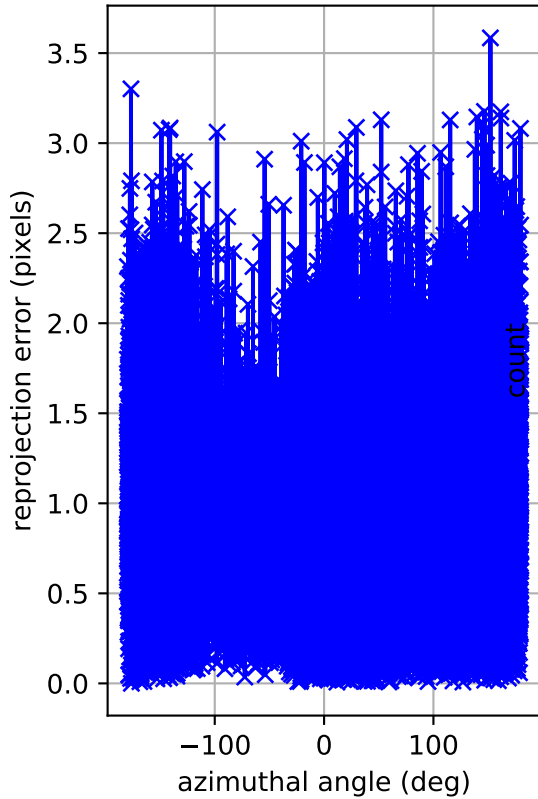
# cam1: reprojection errors



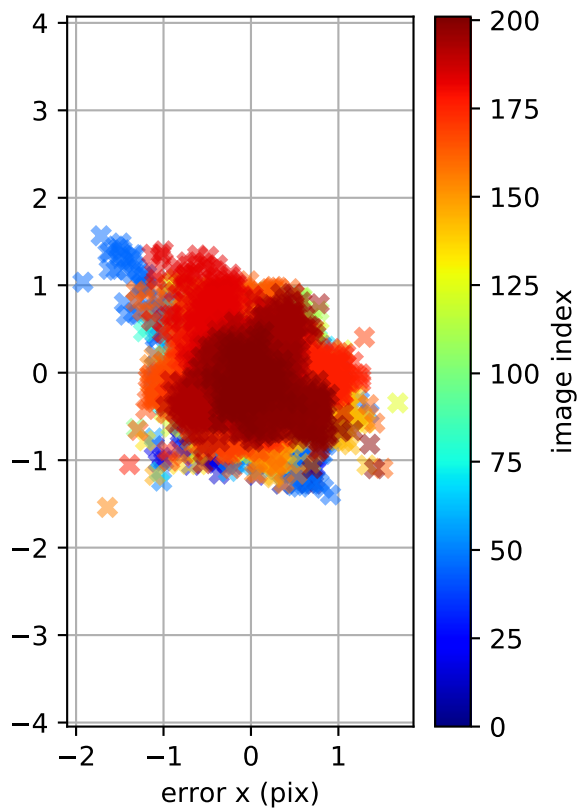
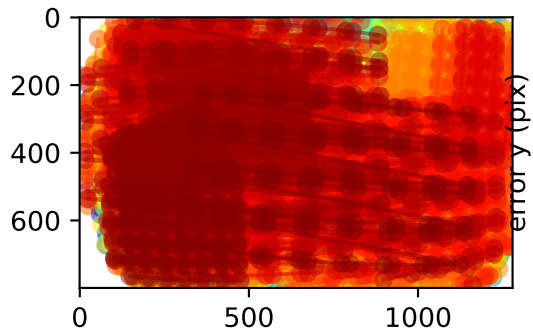
cam2: polar error



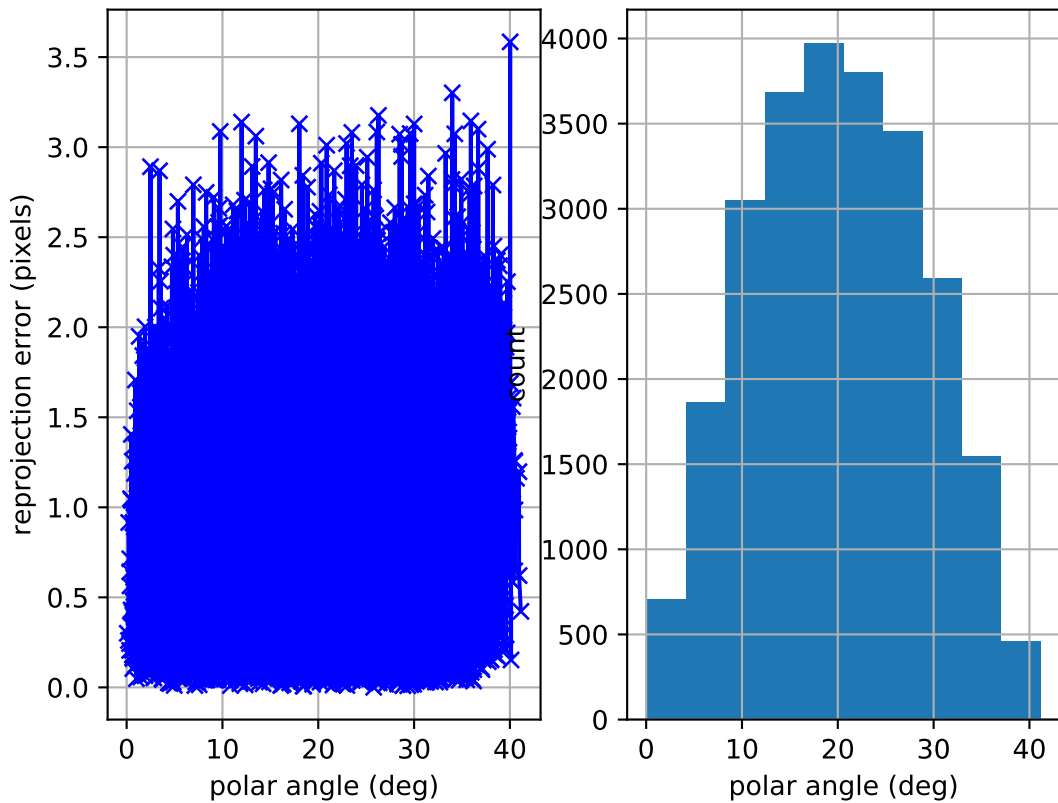
cam2: azimuthal error



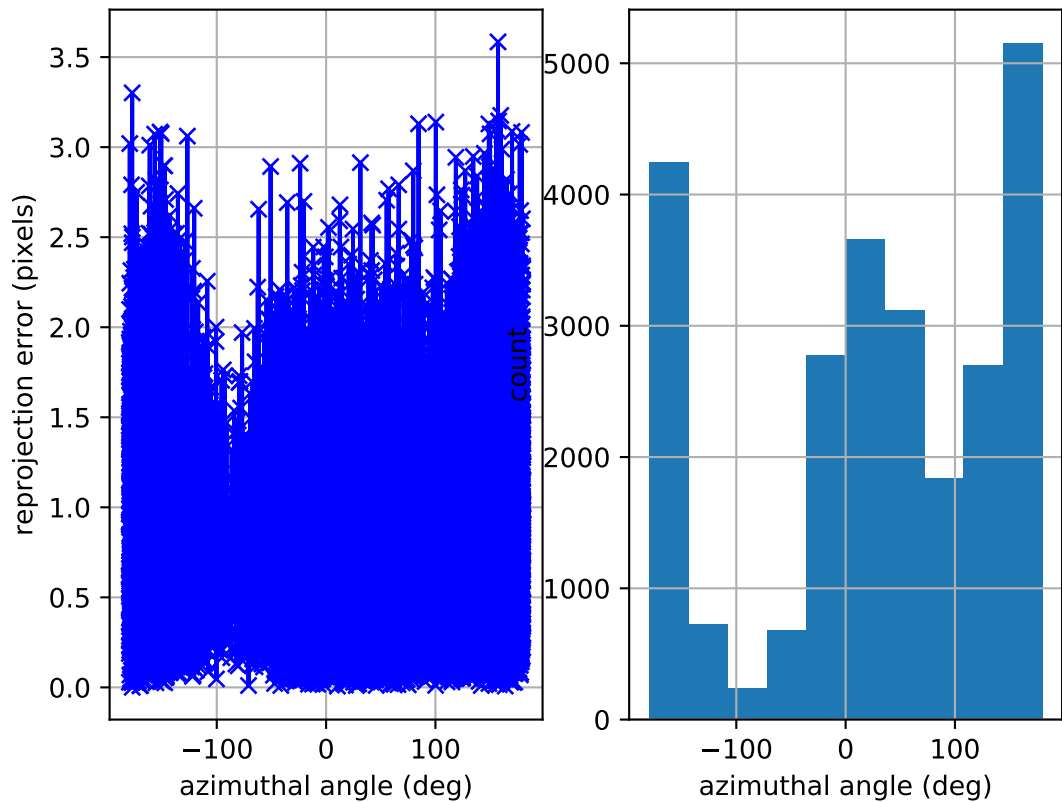
## cam2: reprojection errors



cam3: polar error

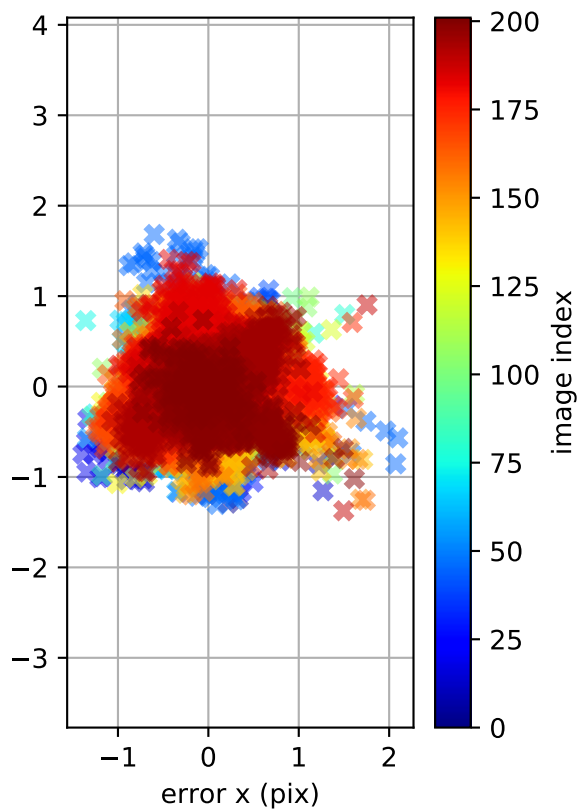
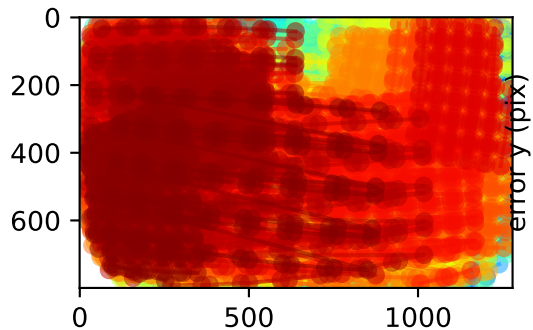


cam3: azimuthal error

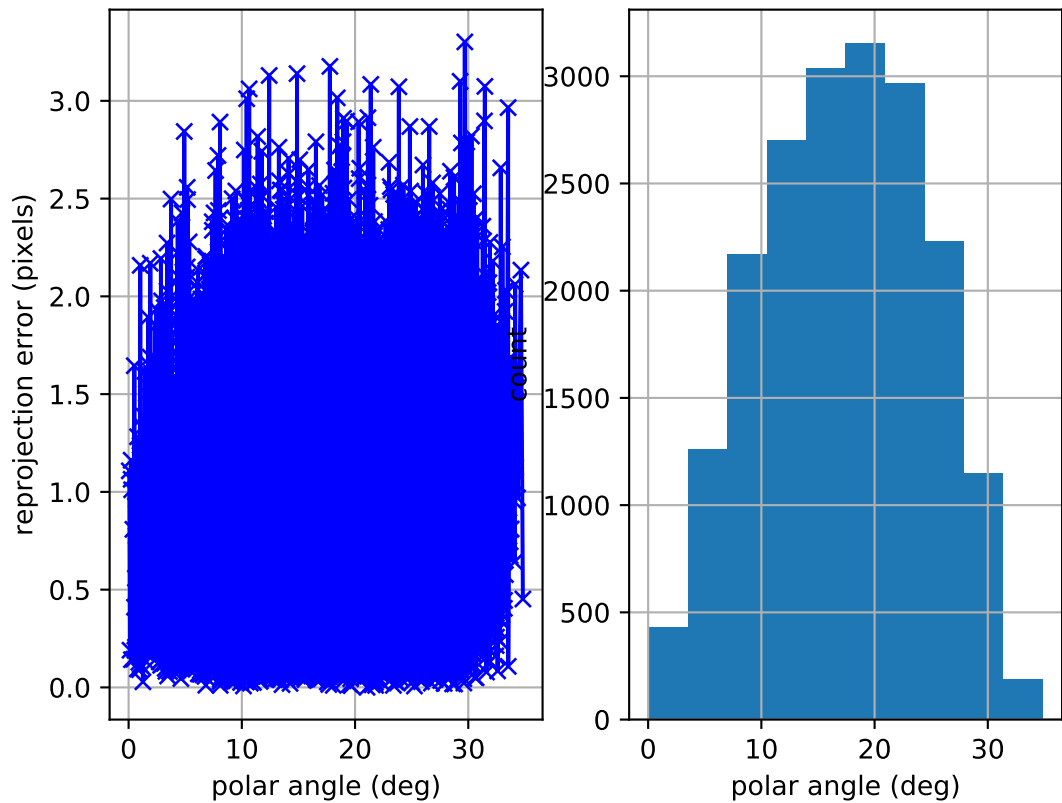




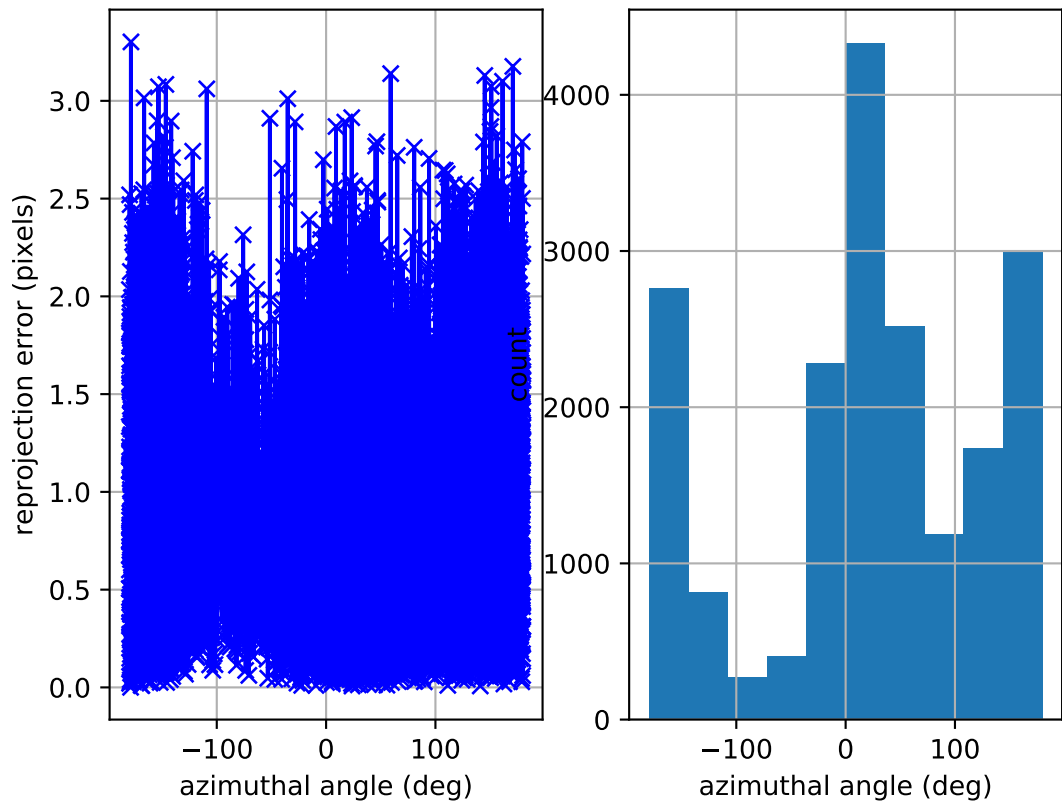
# cam3: reprojection errors



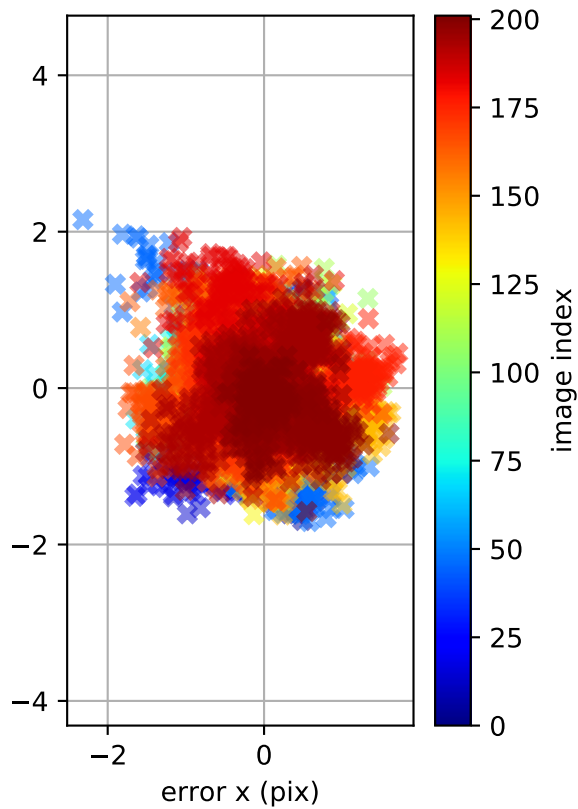
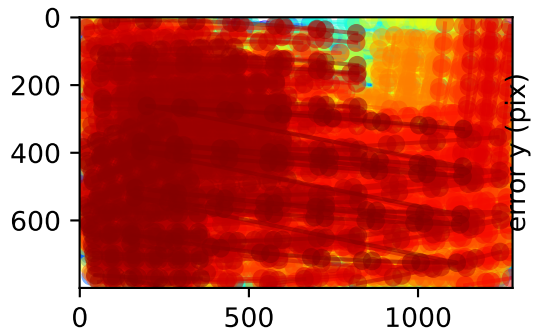
cam4: polar error



cam4: azimuthal error



# cam4: reprojection errors



# Location of removed outlier corners

