

## Calibration results

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### Camera-system parameters:

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

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

distortion: [-0.04808348 0.08491605 0.00021195 -0.00172984] +- [0.00100472 0.00218769 0.00006914 0.00005667]  
projection: [1033.68267355 1033.49697202 633.32457115 366.05170267] +- [0.14311409 0.13852985 0.00535779 0.02269209]

reprojection error: [0.000349, 0.000059] +- [0.763401, 0.614271]

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

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

distortion: [-0.05248536 0.08316828 0.0018384 -0.00102482] +- [0.00107723 0.0024322 0.0000717 0.0000534 ]  
projection: [1032.16302049 1032.64216212 633.10639052 368.24927485] +- [0.14493685 0.14232303 0.00325475 0.02098349]

reprojection error: [0.000405, -0.000043] +- [0.878829, 0.702036]

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

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

distortion: [-0.38985961 0.15111215 -0.00004134 0.0005859 ] +- [0.00047423 0.00074981 0.00004801 0.00003461]  
projection: [1058.66286796 1058.72626398 672.56060547 335.46751649] +- [0.12378466 0.1227987 0.02915067 0.15619817]

reprojection error: [0.000392, -0.000139] +- [0.393562, 0.305112]

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

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

distortion: [-0.38914386 0.14748152 -0.00027546 0.00121203] +- [0.00042871 0.00063633 0.00004714 0.00003249]  
projection: [1053.48424498 1054.16377839 670.4306392 328.06523221] +- [0.1207778 0.12083861 0.02738928 0.15547009]

reprojection error: [0.000340, -0.000308] +- [0.388932, 0.314994]

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

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

distortion: [-0.41507866 0.18609084 0.00004166 0.00011111] +- [0.00080142 0.00196295 0.00005536 0.00003942]  
projection: [1265.47441667 1265.45367834 650.444272 368.01159099] +- [0.13628286 0.13357278 0.00137028 0.01306114]

reprojection error: [0.000224, -0.000240] +- [0.273763, 0.228867]

#### baseline T\_1\_0:

q: [-0.00138062 0.00122523 -0.00037904 0.99999822] +- [0.00005468 0.00004597 0.00004147]

t: [-0.12030512 0.00085321 -0.00012173] +- [0.00002957 0.00002849 0.00011533]

baseline T\_2\_1:

q: [ 0.00024778 -0.00203402 -0.00524005 0.99998417] +- [0.0001352 0.00004823 0.00003869]

t: [0.12006776 0.06938411 0.00414593] +- [0.00002739 0.00002815 0.00010905]

baseline T\_3\_2:

q: [ 0.00022005 -0.00250936 0.00025731 0.99999679] +- [0.00029122 0.00006563 0.00003197]

t: [-0.11999039 -0.00004913 0.0012614 ] +- [0.0000248 0.00002598 0.00009661]

baseline T\_4\_3:

q: [0.00144197 0.00513962 0.00024241 0.99998572] +- [0.00014647 0.00004391 0.00003262]

t: [0.08888568 0.00617406 0.00298109] +- [0.00002321 0.00002466 0.00009764]

Target configuration

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Type: aprilgrid

Tags:

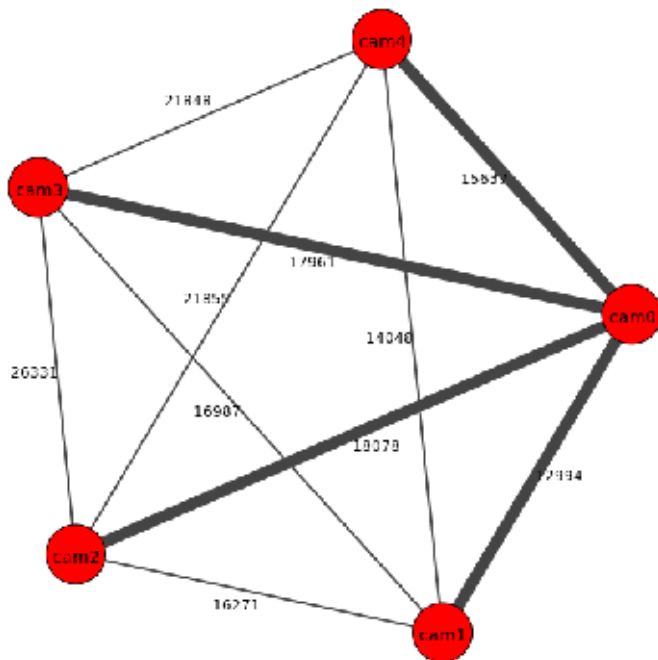
Rows: 5

Cols: 7

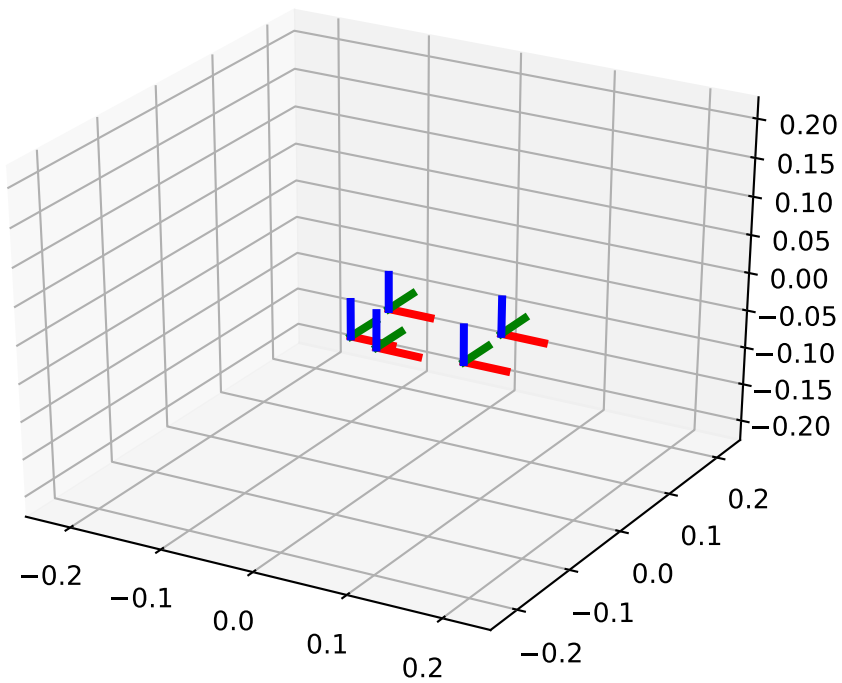
Size: 0.04 [m]

Spacing 0.01 [m]

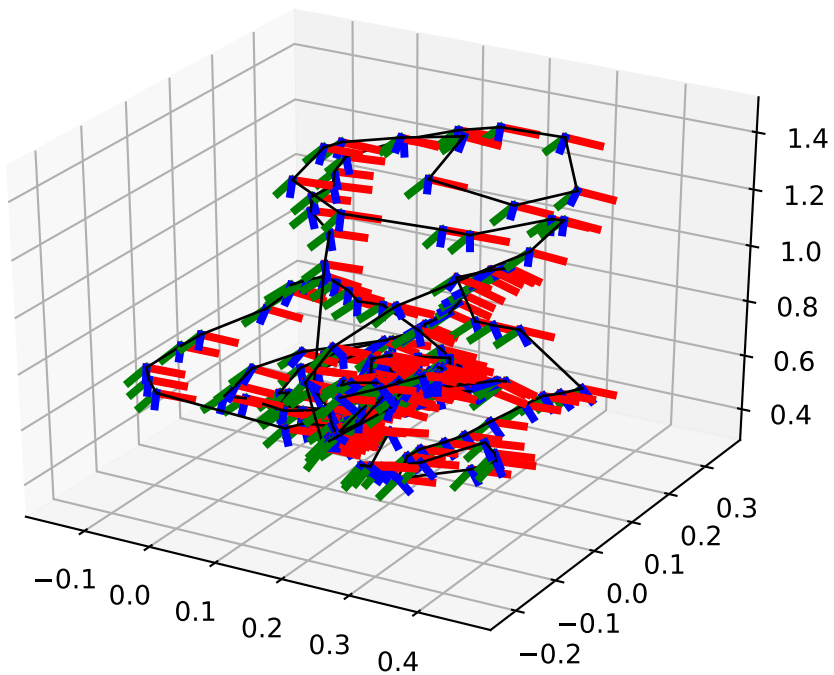
Inter-camera observations graph (edge weight=#mutual obs.)



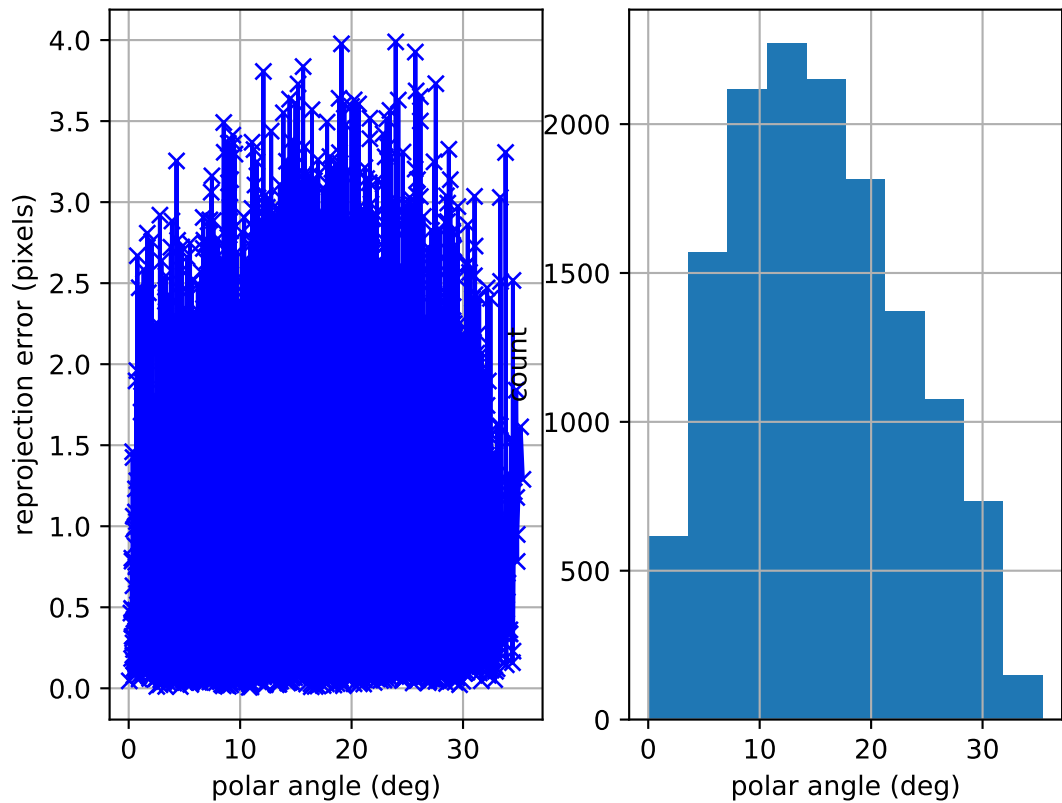
camera system



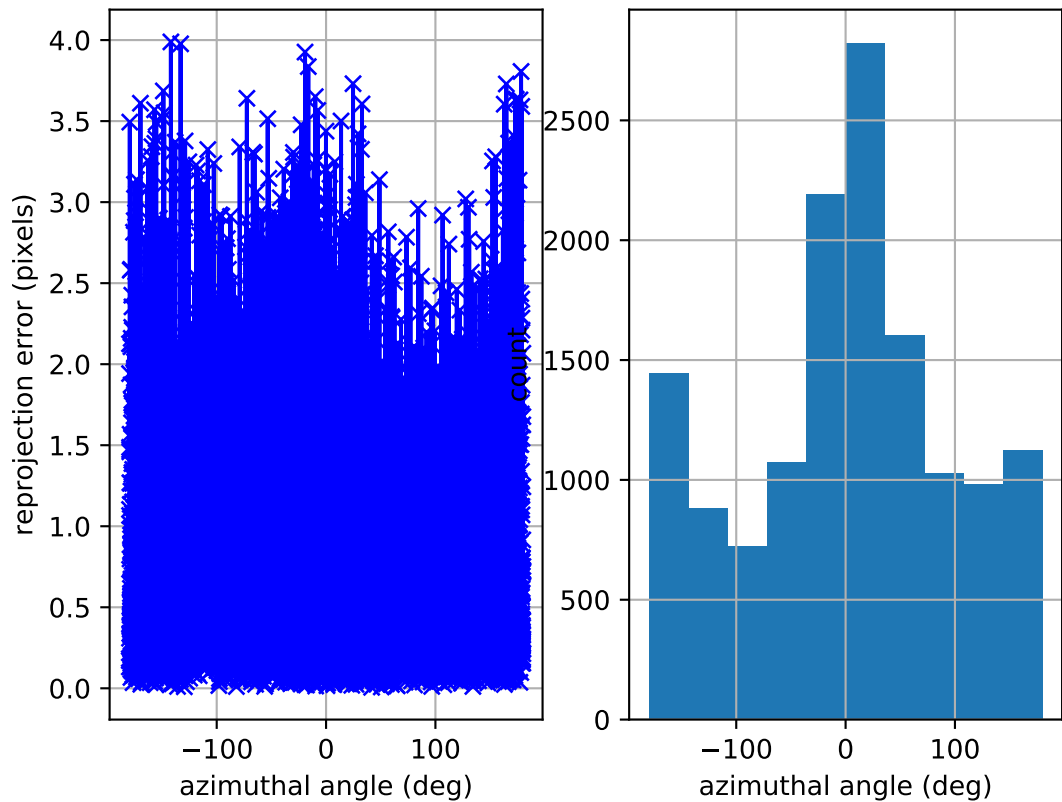
cam0: estimated poses



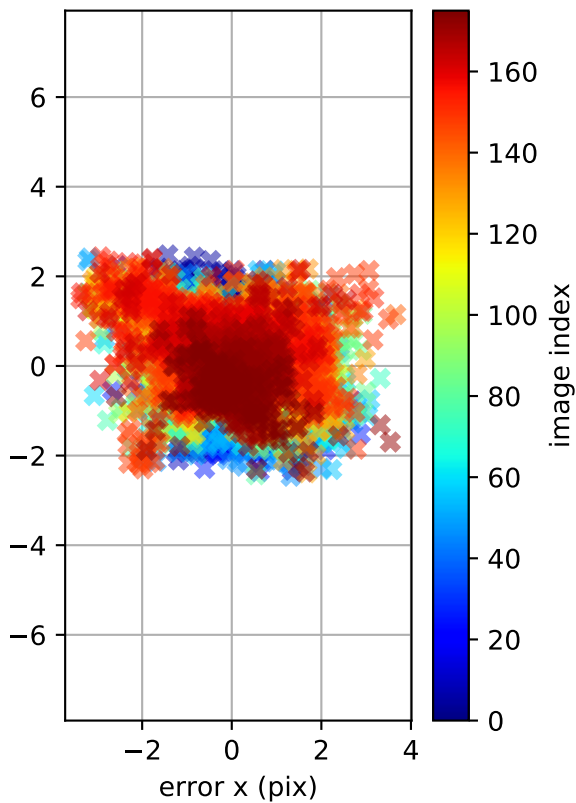
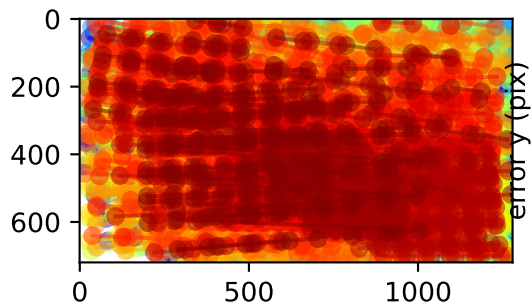
cam0: polar error



cam0: azimuthal error

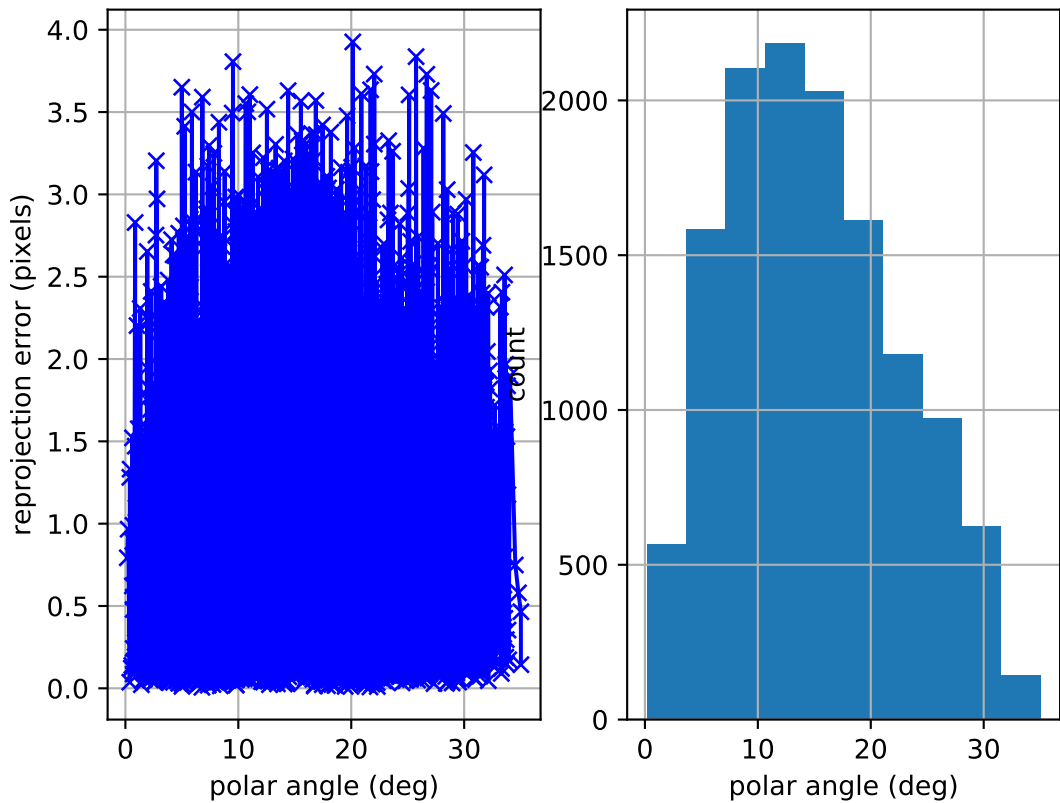


# cam0: reprojection errors

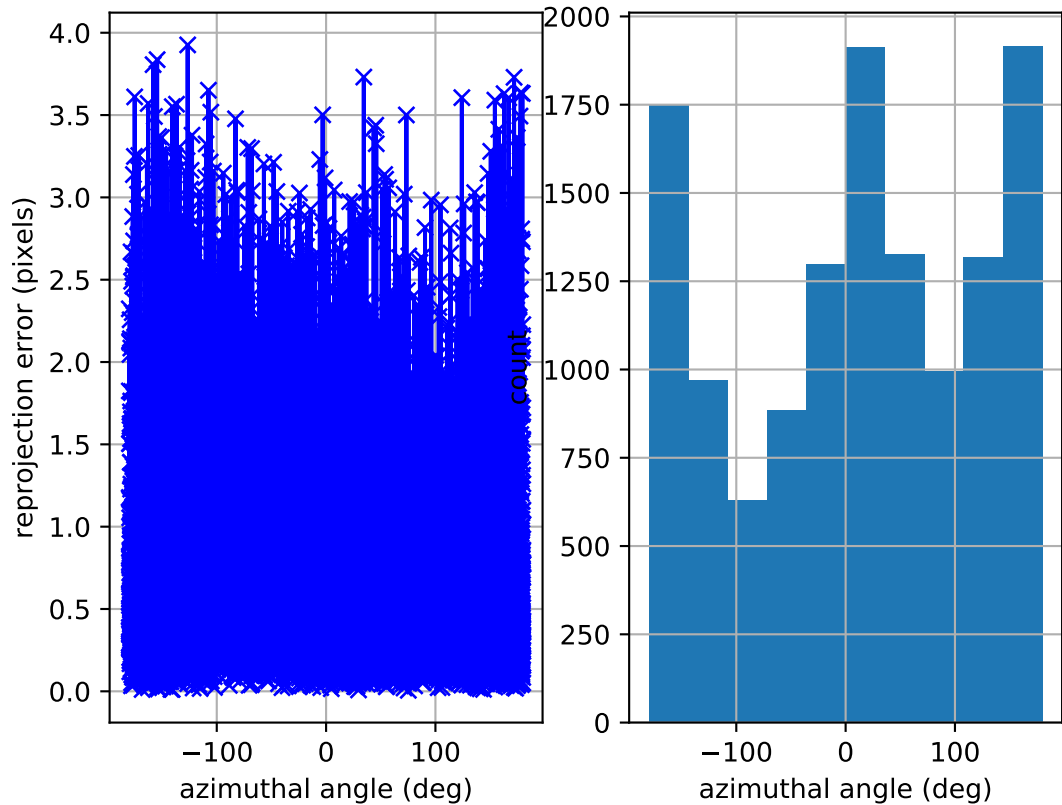




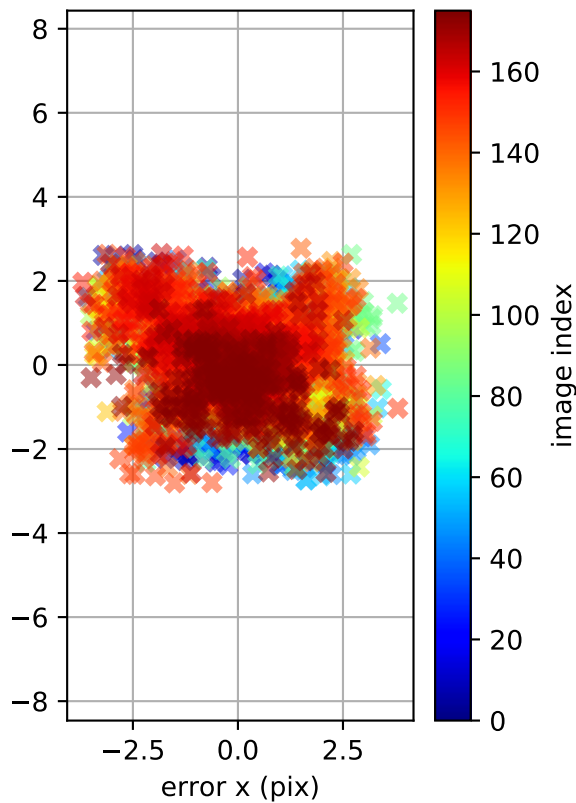
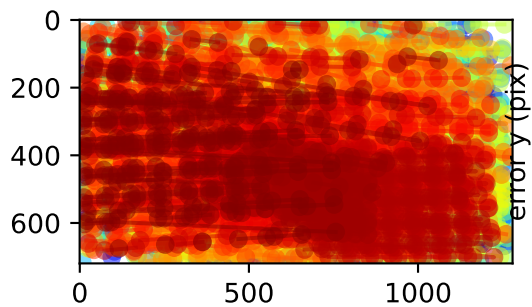
cam1: polar error



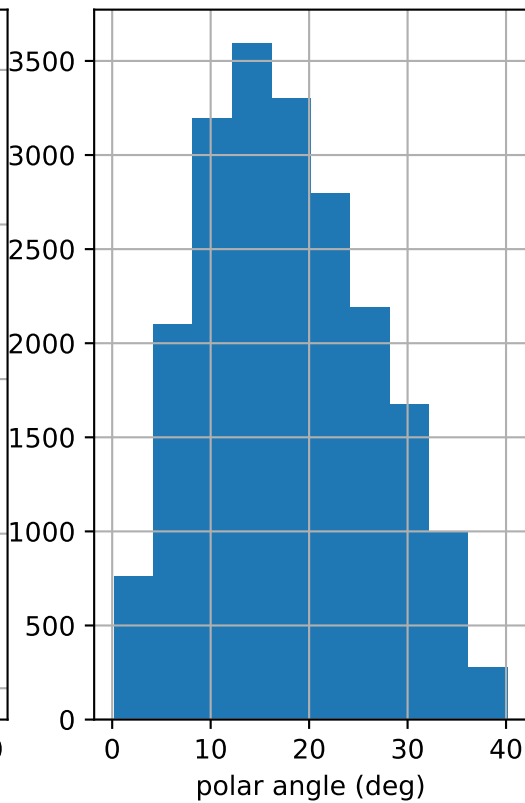
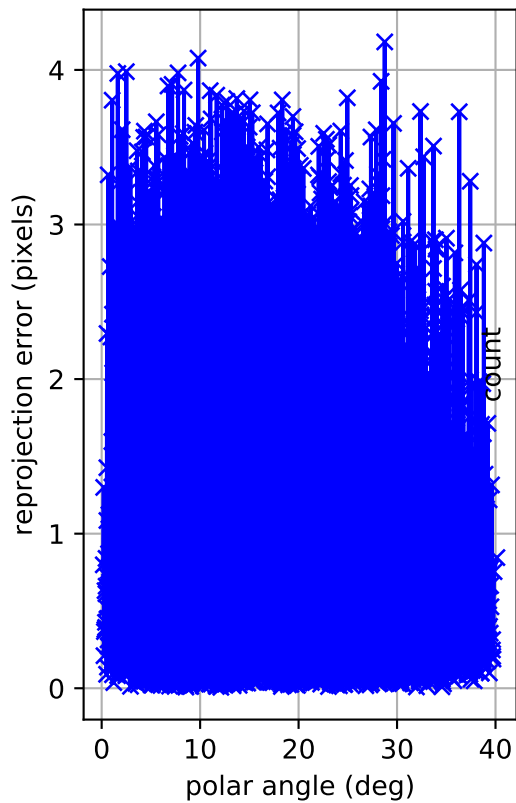
cam1: azimuthal error



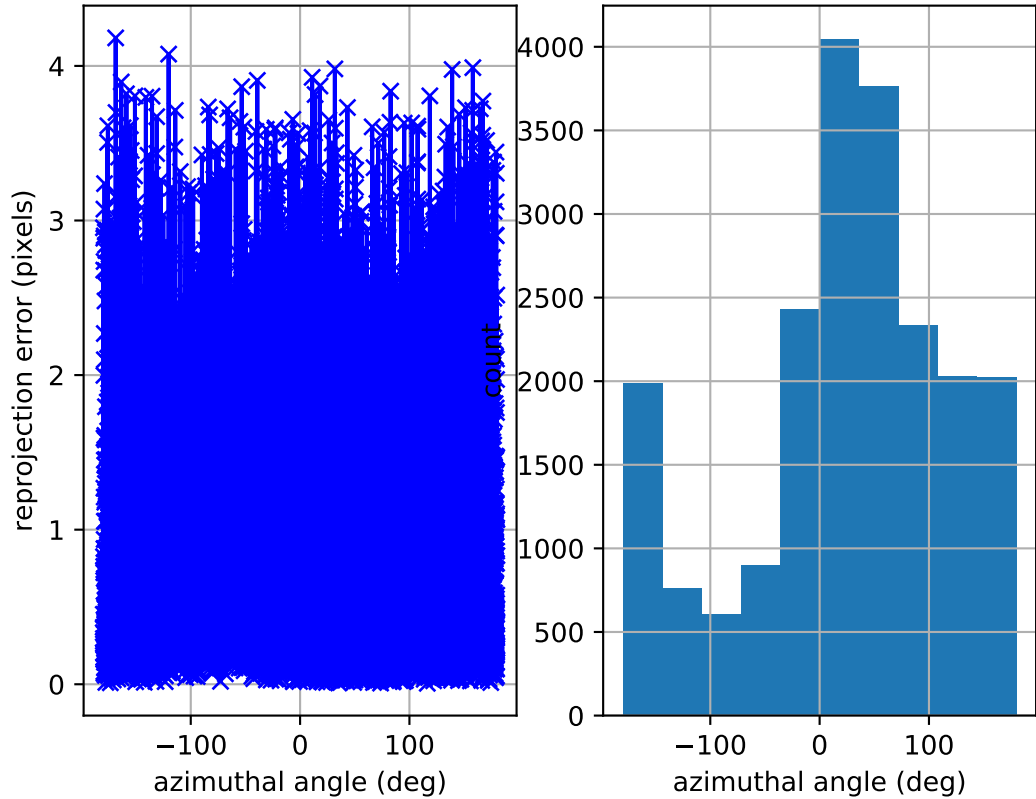
# cam1: reprojection errors



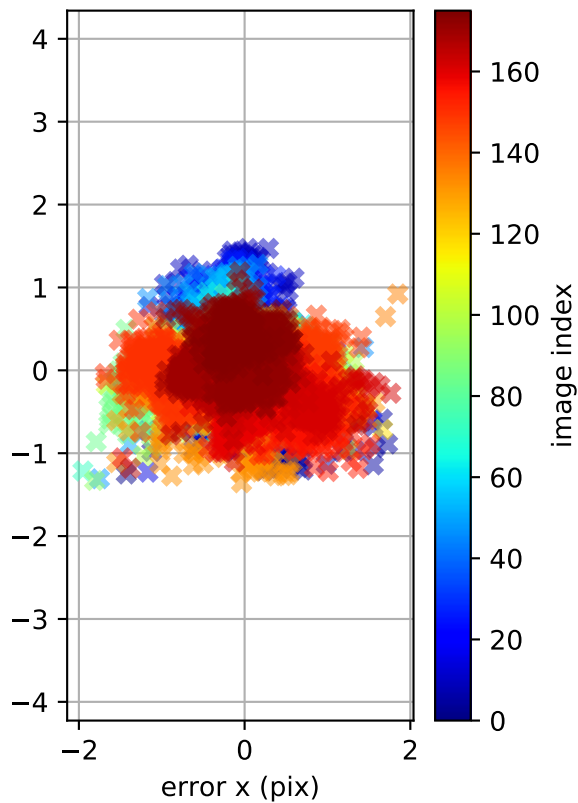
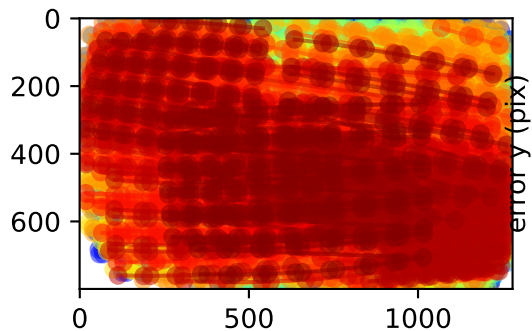
cam2: polar error



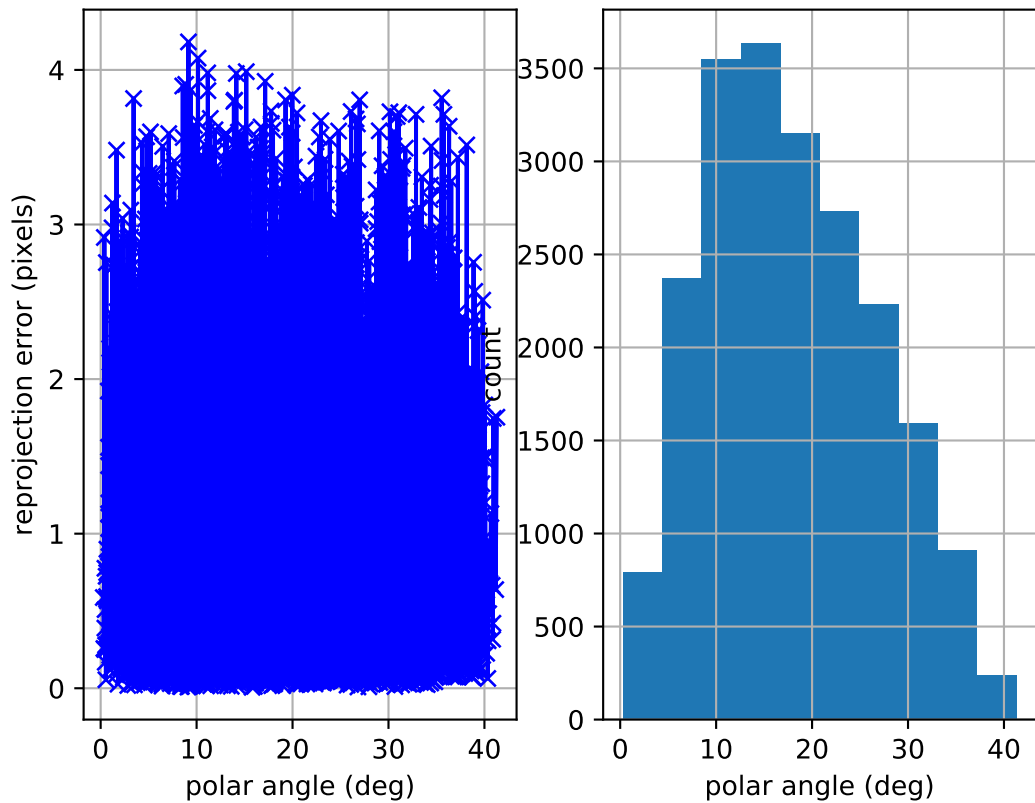
cam2: azimuthal error



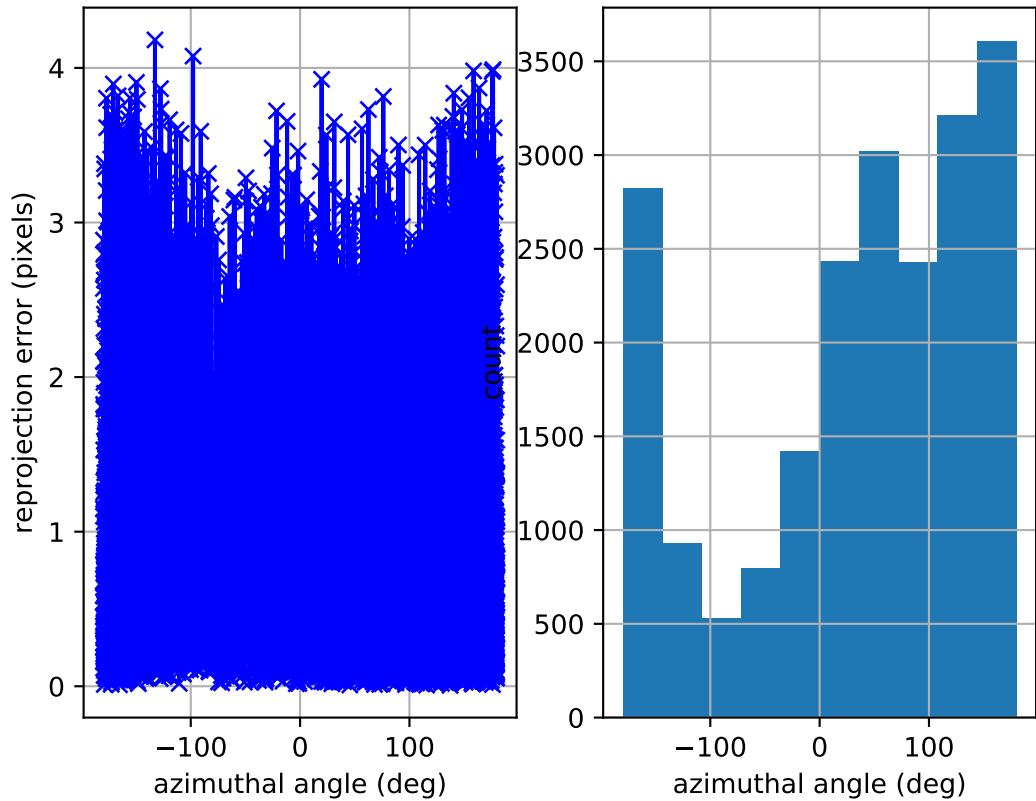
## cam2: reprojection errors



### cam3: polar error

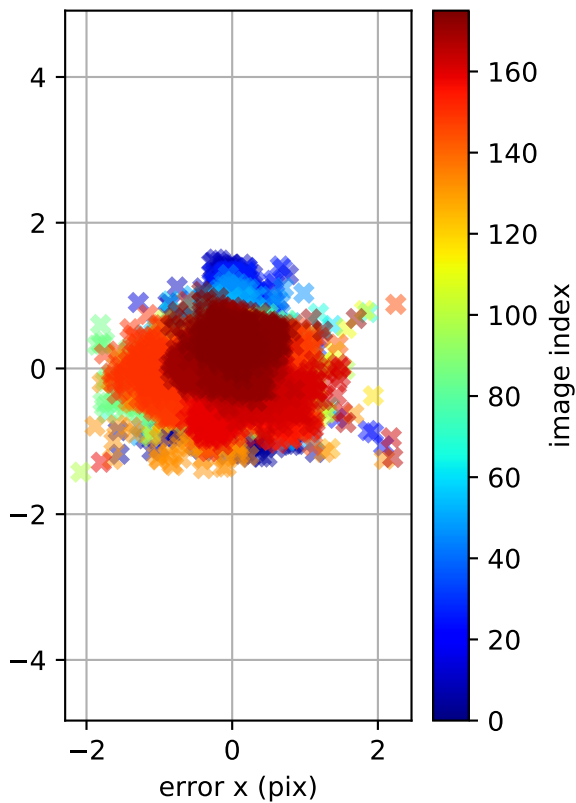
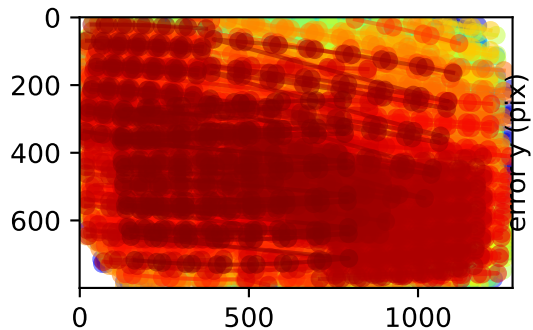


cam3: azimuthal error

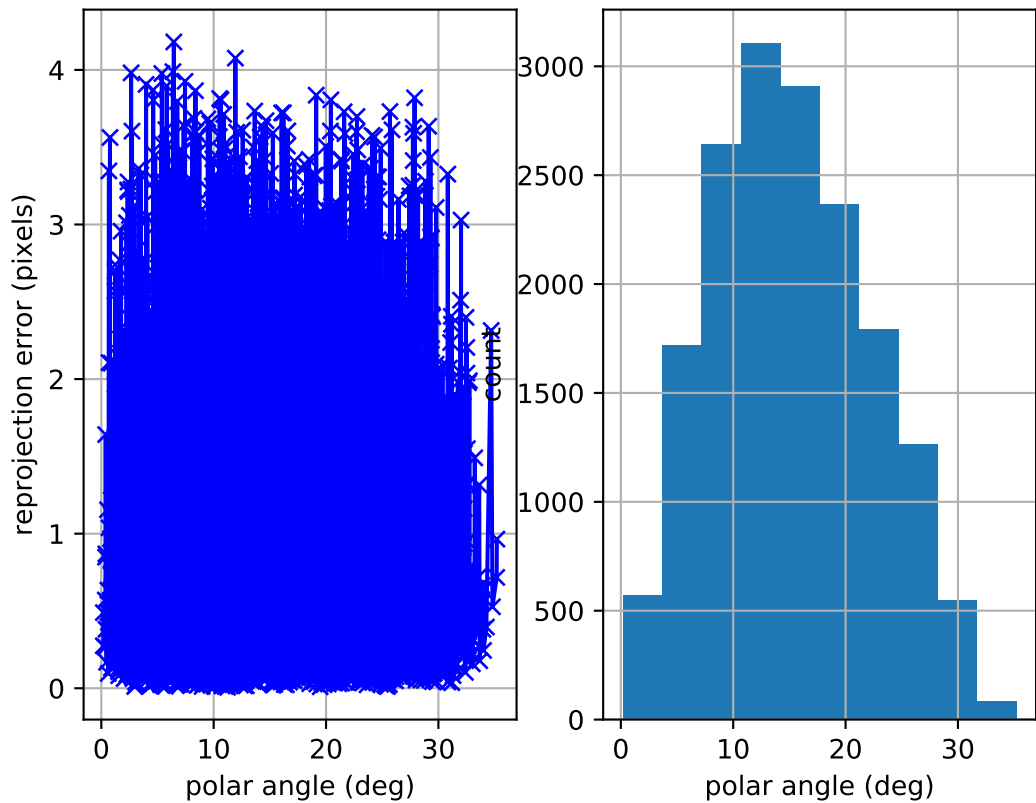




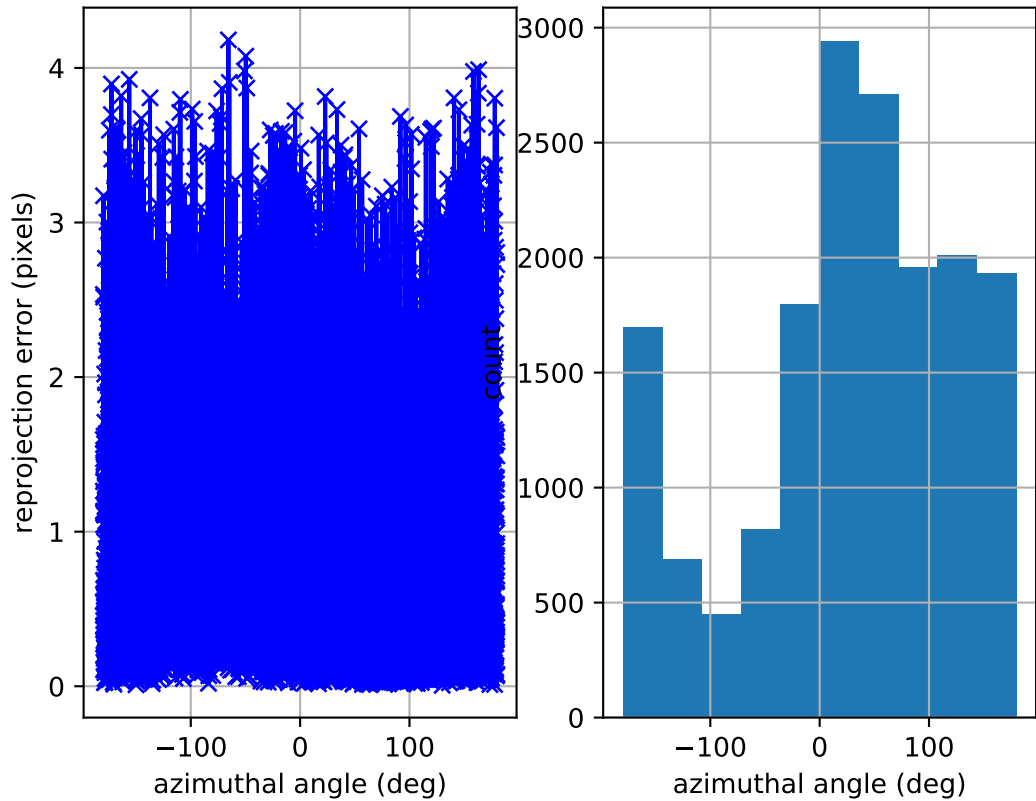
# cam3: reprojection errors



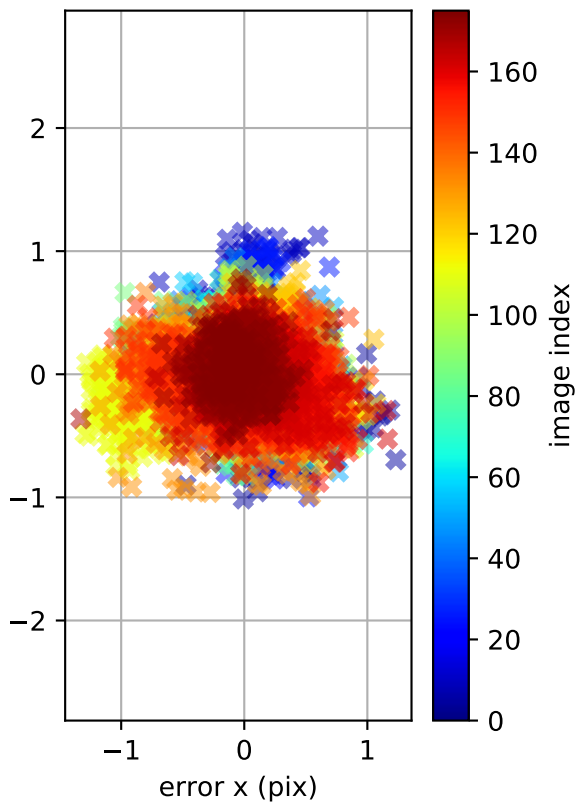
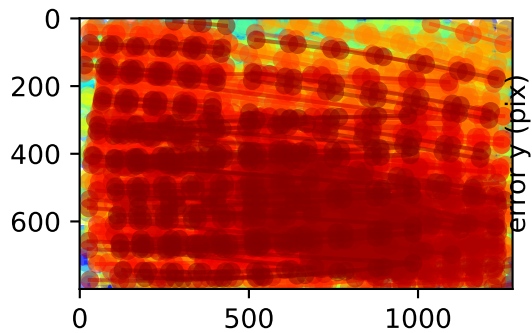
cam4: polar error



cam4: azimuthal error



# cam4: reprojection errors



# Location of removed outlier corners

