

## Calibration results

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### Camera-system parameters:

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

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

distortion: [-0.05220203 0.08858383 -0.00006036 -0.0004581 ] +- [0.00112853 0.00268699 0.00008257 0.00004999]  
projection: [1032.09929551 1031.39209583 636.47636903 361.12220067] +- [0.15089396 0.14862461 0.00647575 0.06247333]

reprojection error: [-0.000044, -0.000001] +- [0.591686, 0.522502]

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

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

distortion: [-0.05764699 0.08742015 0.00008705 0.00097248] +- [0.00110615 0.00251694 0.00008602 0.00005077]  
projection: [1031.57914607 1031.0377026 639.24448554 364.29600843] +- [0.16605527 0.16267572 0.00670985 0.08118039]

reprojection error: [0.000045, -0.000016] +- [0.640947, 0.576805]

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

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

distortion: [-0.39951658 0.17068582 0.00027609 0.00017693] +- [0.00057428 0.00114899 0.0000555 0.00003004]  
projection: [1057.86857168 1057.76325541 678.48718136 333.83240056] +- [0.1289435 0.12602268 0.04541559 0.23682031]

reprojection error: [0.000096, -0.000015] +- [0.177001, 0.160795]

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

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

distortion: [-0.39477275 0.15729816 0.00015809 0.00073495] +- [0.00044847 0.00074009 0.00005135 0.0000312 ]  
projection: [1052.4402019 1052.50035135 675.80280453 326.38308762] +- [0.13819519 0.13339781 0.02908265 0.24343497]

reprojection error: [0.000108, -0.000048] +- [0.211654, 0.176854]

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

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

distortion: [-0.41817867 0.19325443 0.00041248 -0.00038386] +- [0.00073969 0.00193265 0.00005364 0.0000326 ]  
projection: [1263.80029715 1263.33722497 656.43049364 364.93639743] +- [0.13684546 0.1331824 0.03138036 0.17974817]

reprojection error: [0.000058, -0.000023] +- [0.194516, 0.176621]

#### baseline T\_1\_0:

q: [-0.00061432 0.00294653 -0.00025992 0.99999544] +- [0.00011388 0.00006815 0.00004518]

t: [-0.12011853 0.00092495 -0.0005678 ] +- [0.00003509 0.00003306 0.00011846]

baseline T\_2\_1:

q: [ 0.0005039 -0.00372038 -0.00482308 0.99998132] +- [0.00024585 0.00007863 0.00004124]

t: [0.12019771 0.06917936 0.00403851] +- [0.00003201 0.00003112 0.00011016]

baseline T\_3\_2:

q: [-0.00018236 0.00049791 0.0003545 0.9999998 ] +- [0.00033538 0.00007674 0.00003521]

t: [-0.11996185 -0.00011313 0.00023493] +- [0.00002786 0.00002686 0.00009516]

baseline T\_4\_3:

q: [0.00202262 0.00150374 0.00029379 0.99999678] +- [0.00033171 0.00006523 0.00003399]

t: [0.088834 0.00621991 0.00303376] +- [0.00002711 0.00002566 0.00009432]

Target configuration

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Type: aprilgrid

Tags:

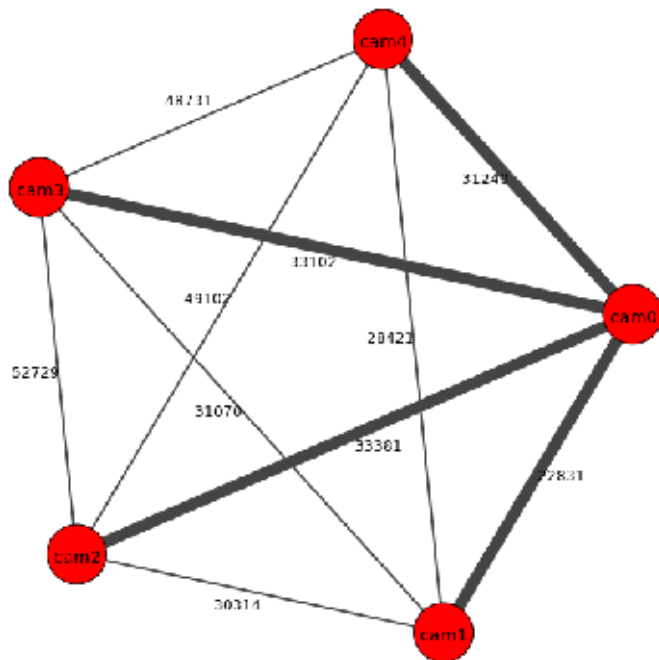
Rows: 5

Cols: 7

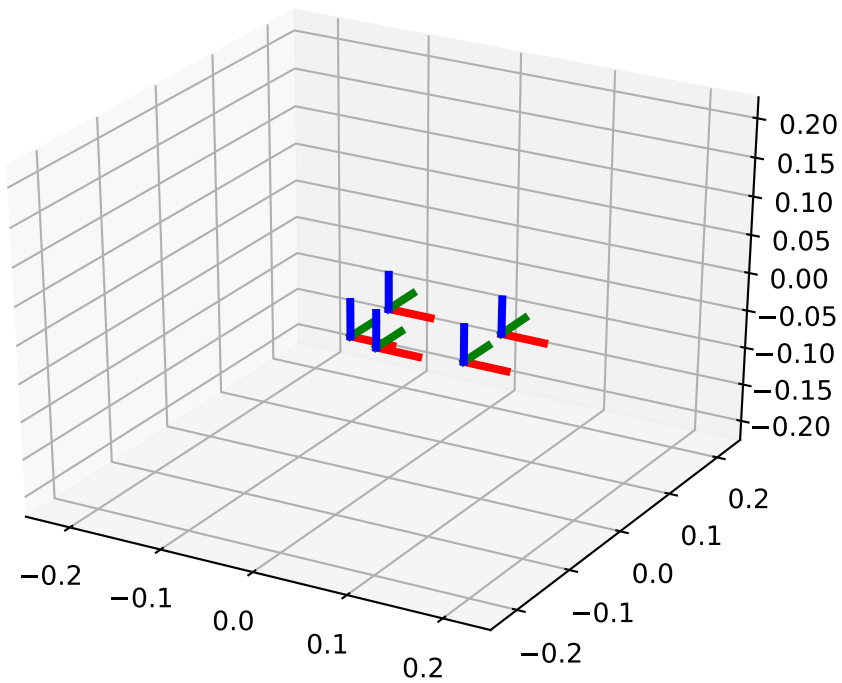
Size: 0.04 [m]

Spacing 0.01 [m]

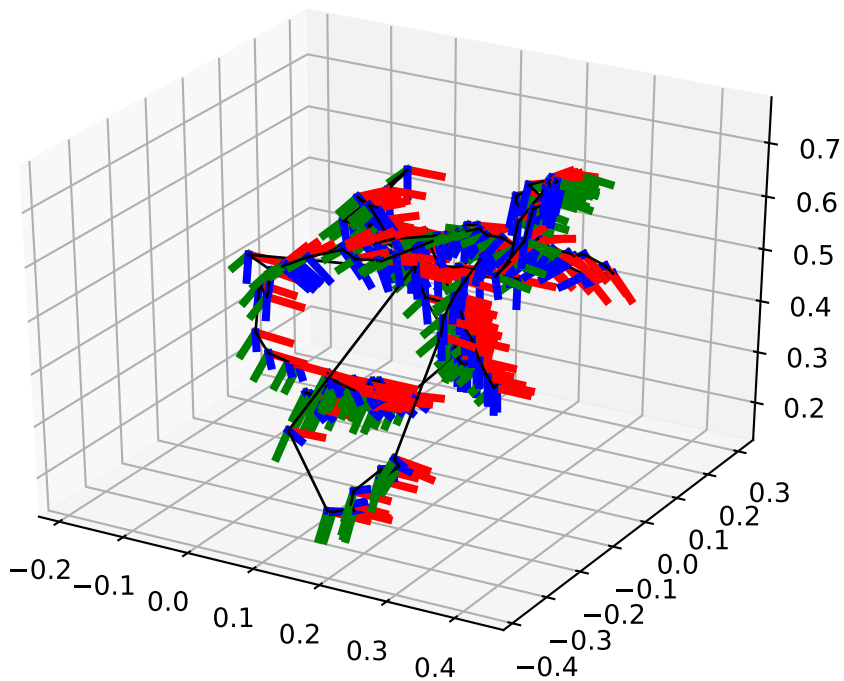
Inter-camera observations graph (edge weight=#mutual obs.)



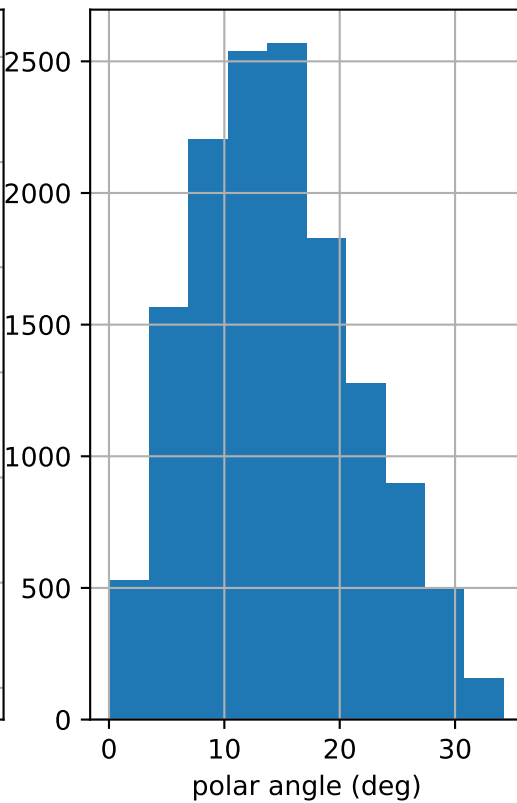
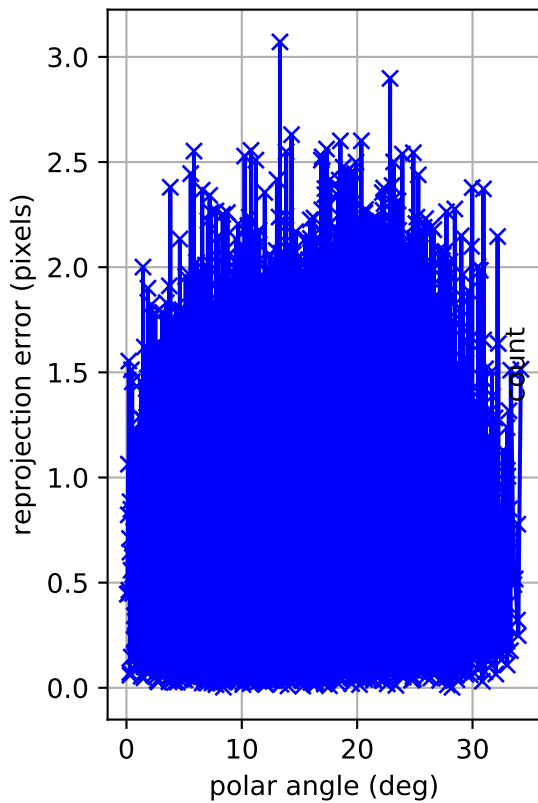
camera system



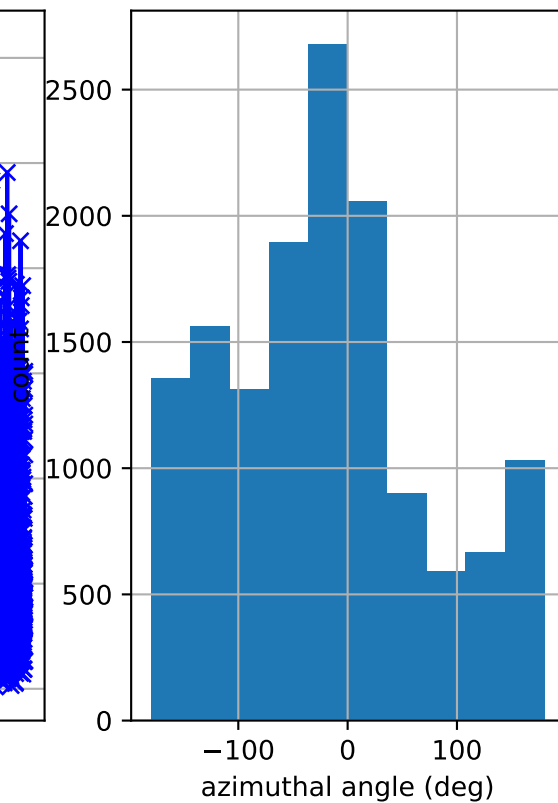
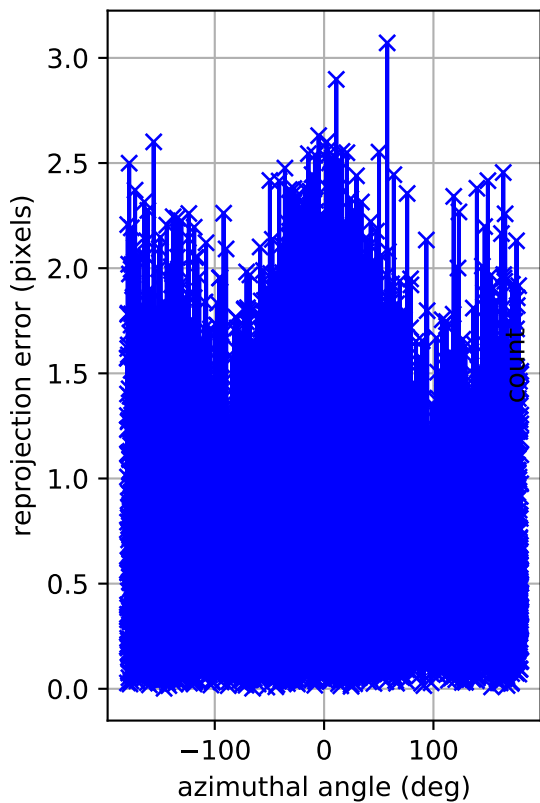
cam0: estimated poses



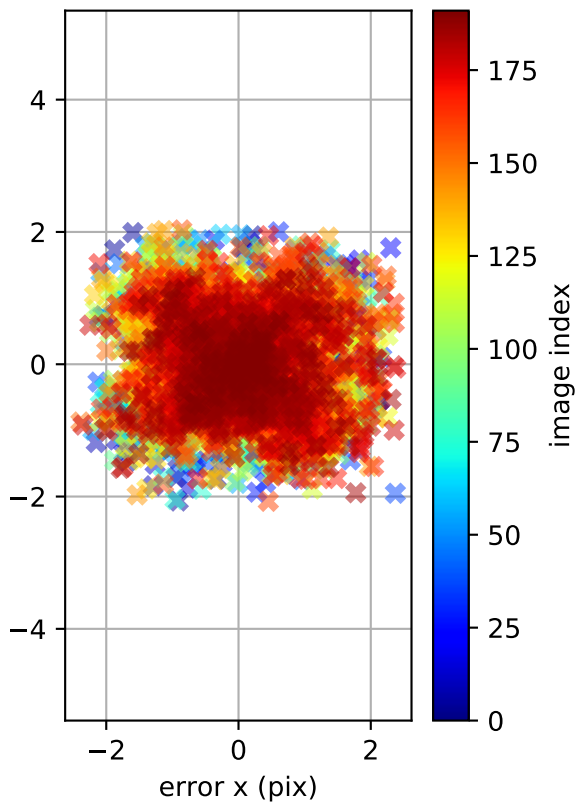
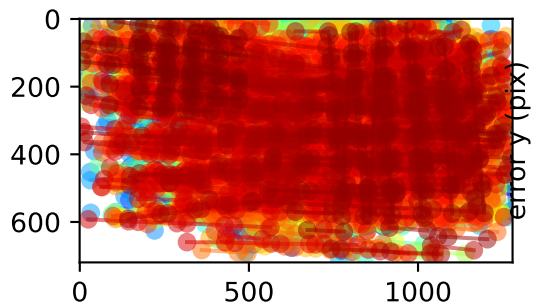
cam0: polar error



cam0: azimuthal error

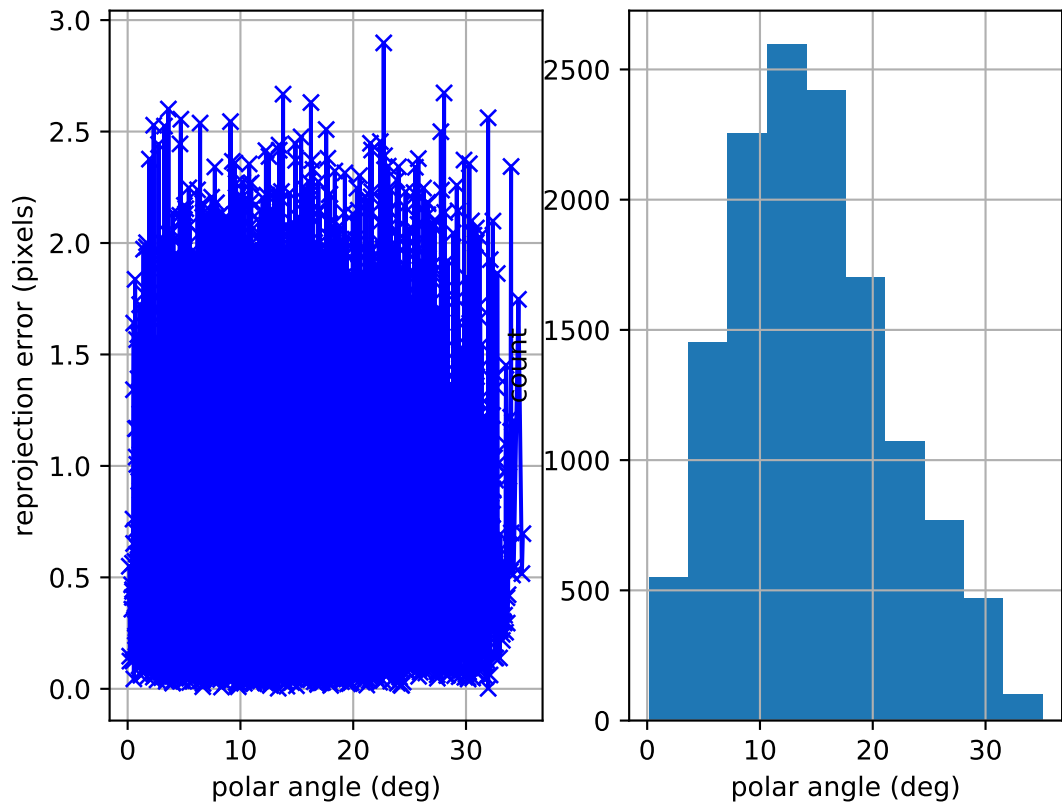


# cam0: reprojection errors

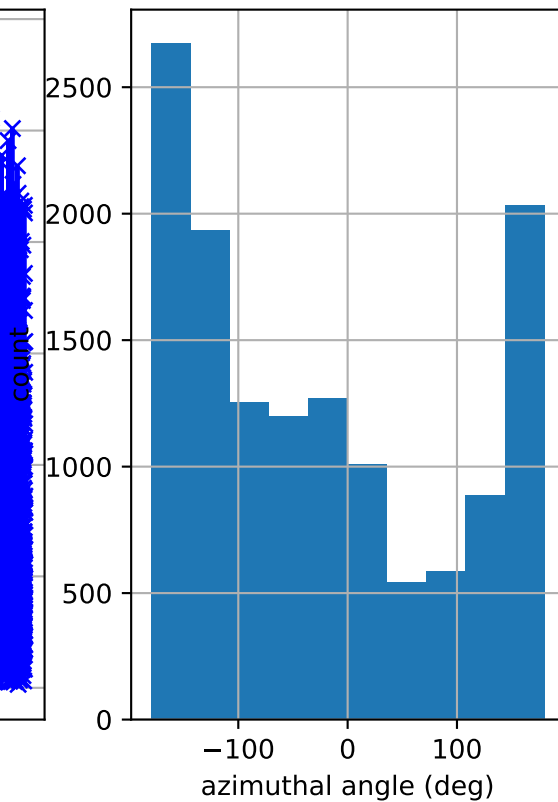
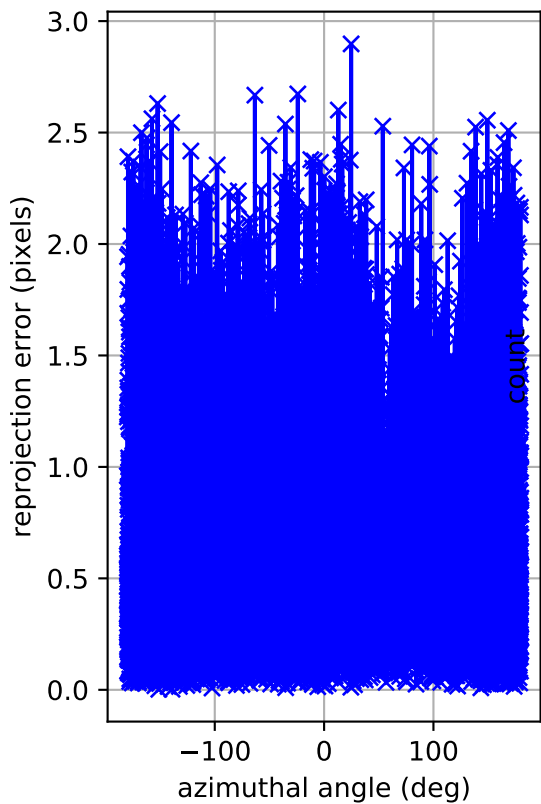




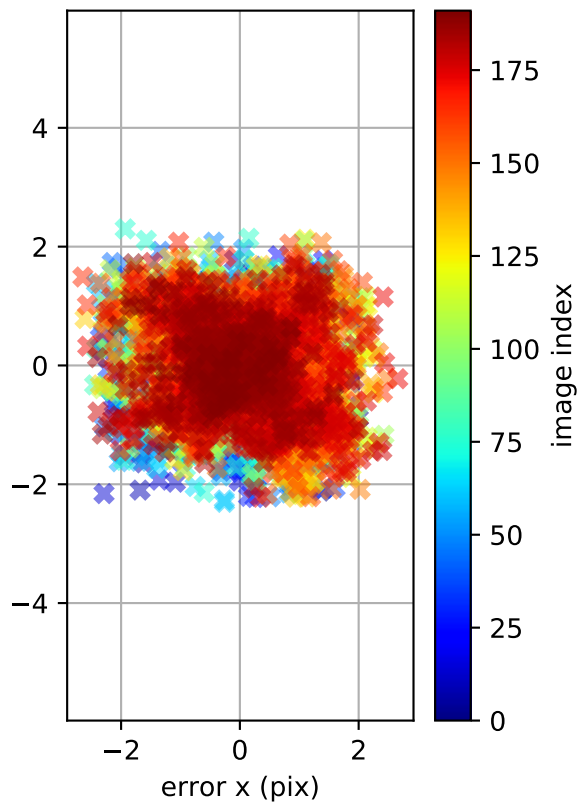
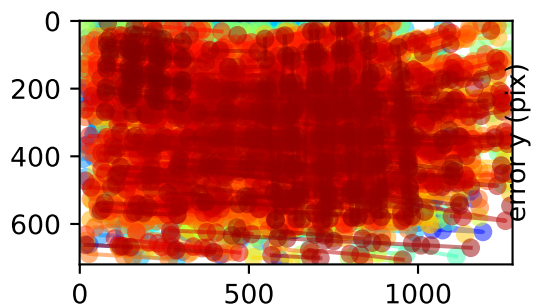
cam1: polar error



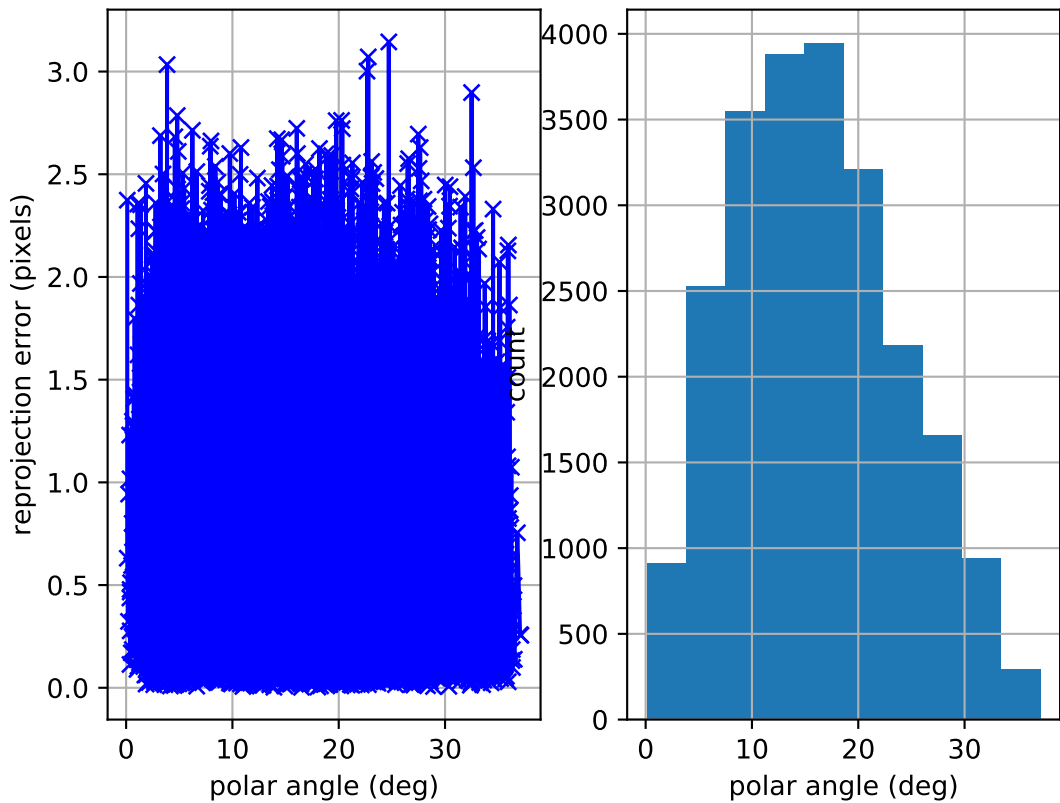
cam1: azimuthal error



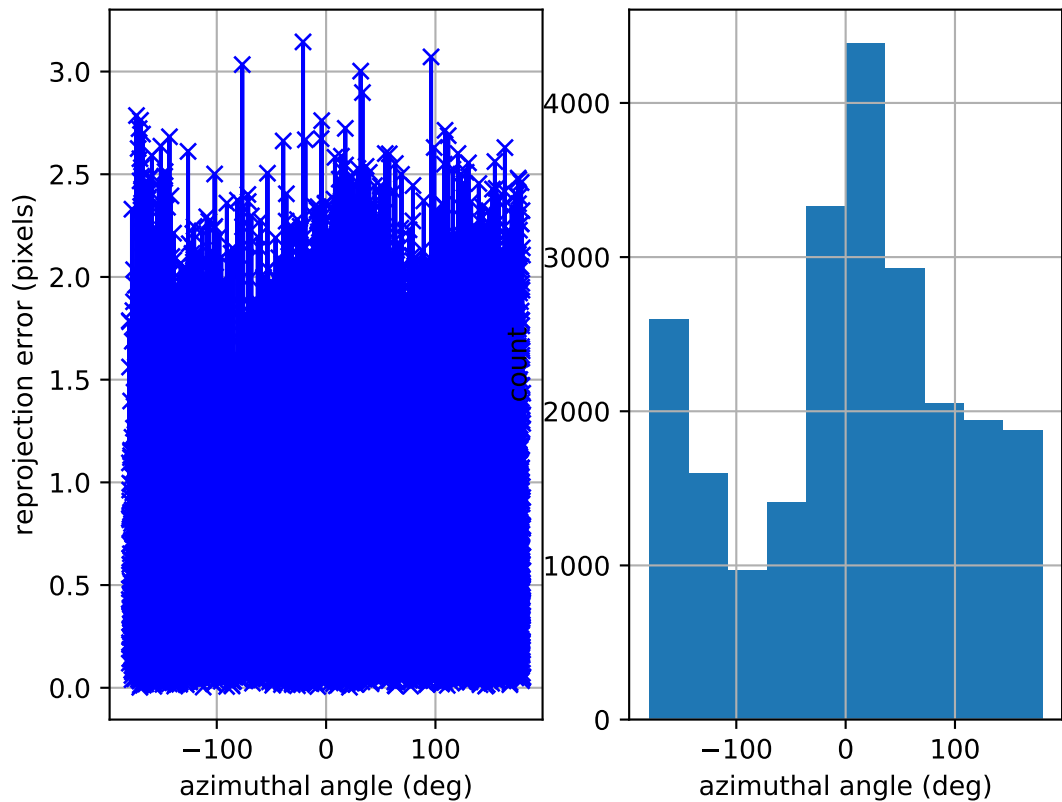
# cam1: reprojection errors



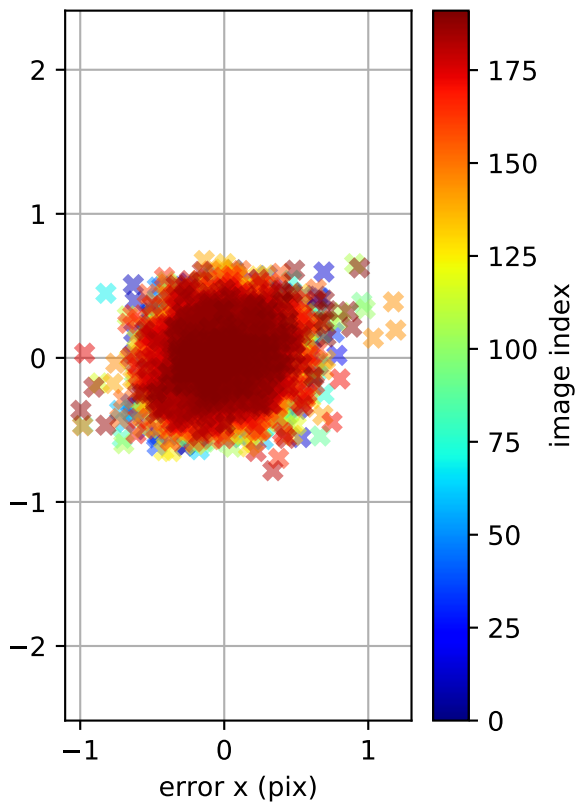
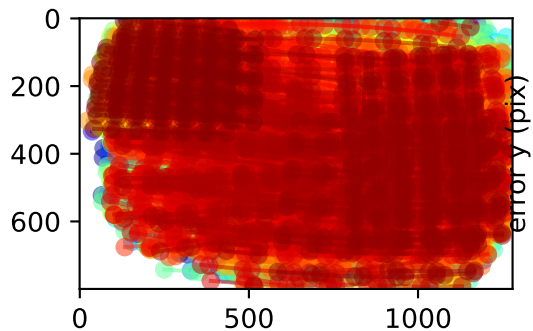
cam2: polar error



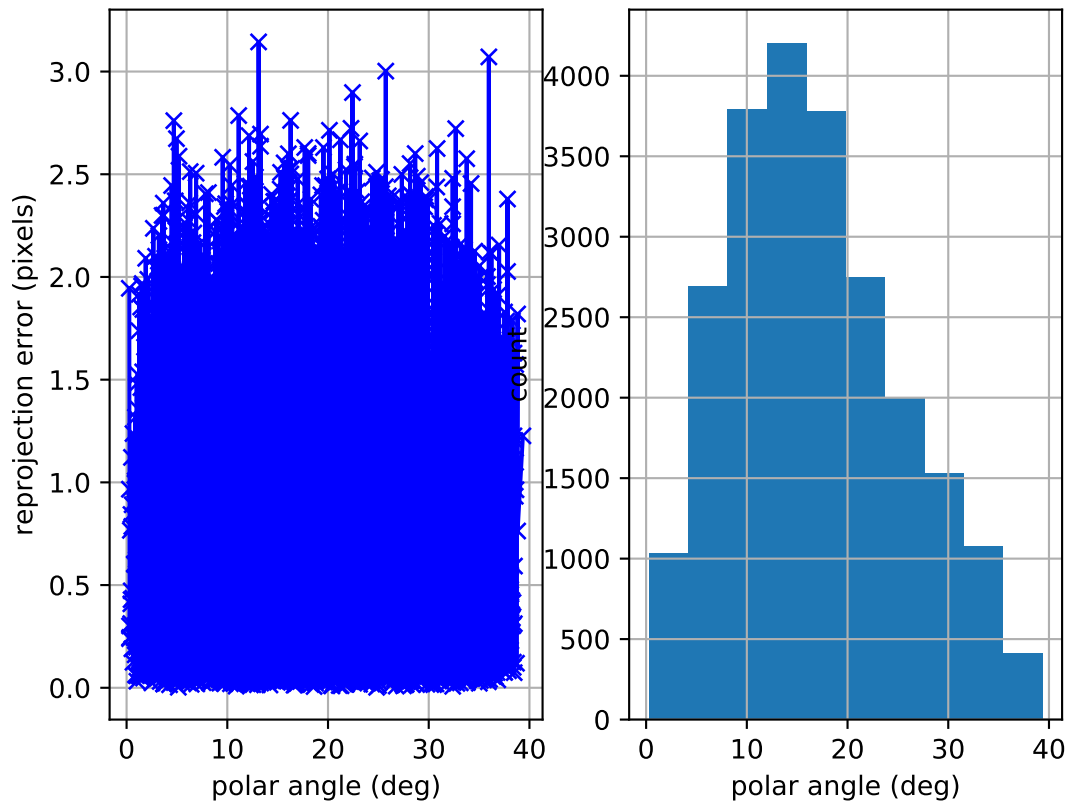
cam2: azimuthal error



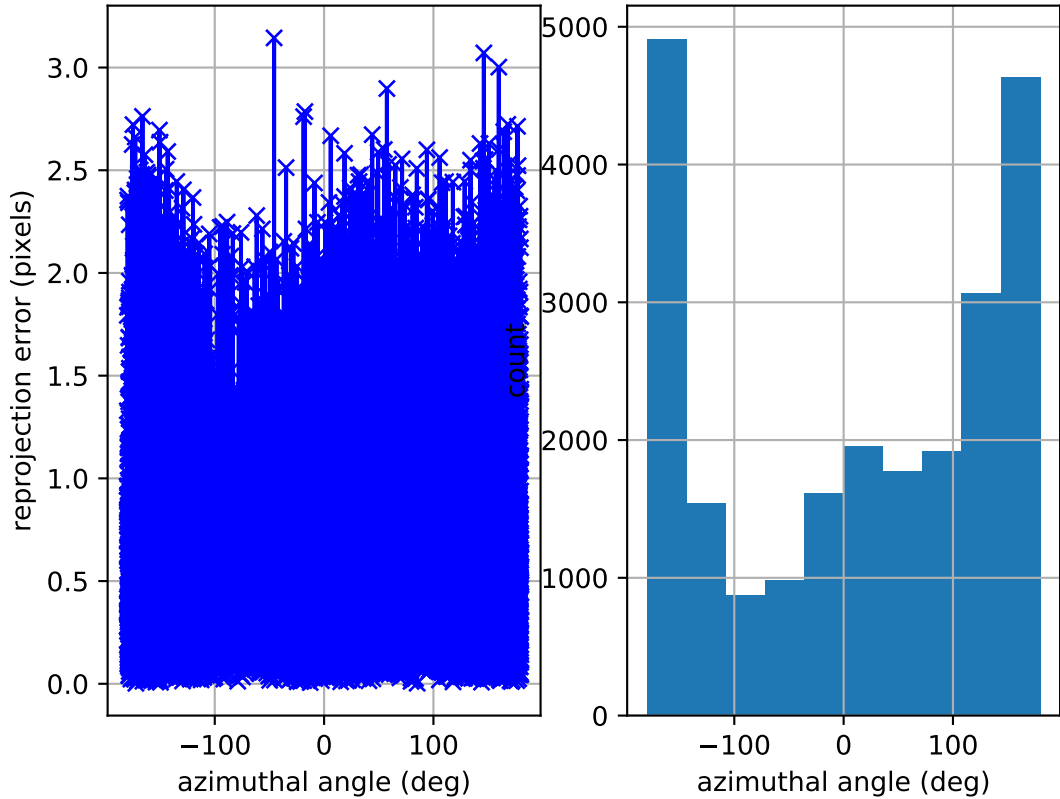
## cam2: reprojection errors



cam3: polar error

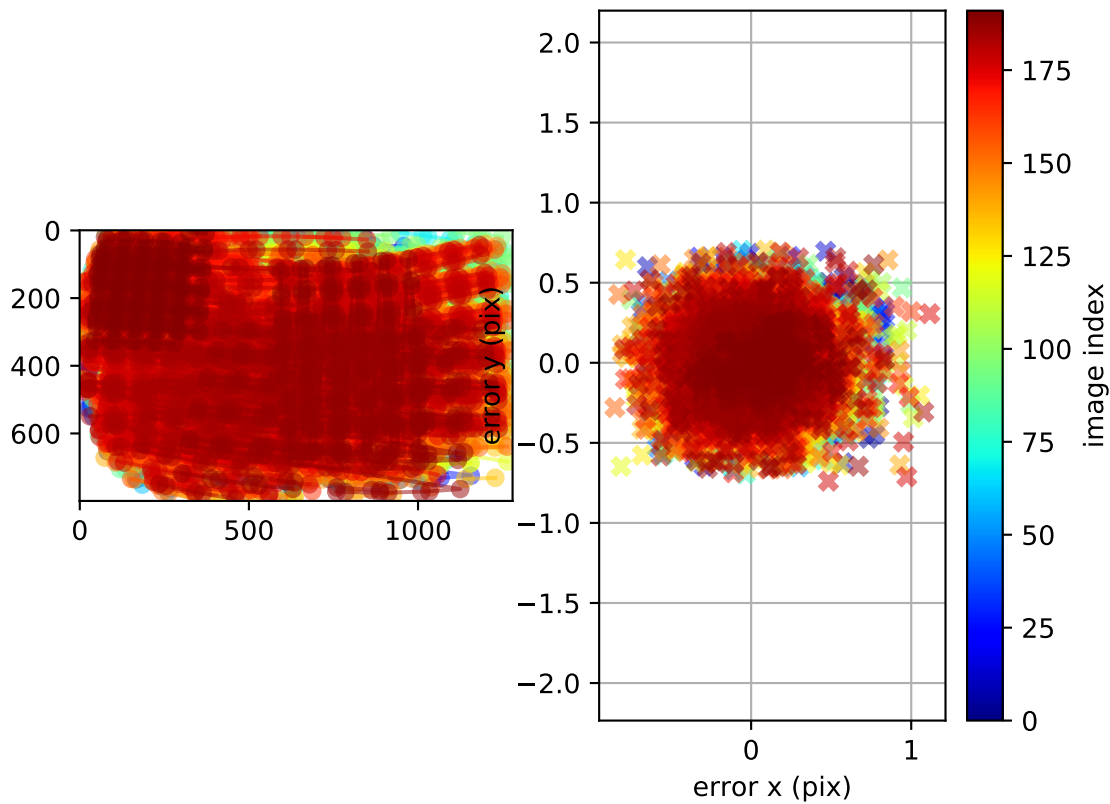


cam3: azimuthal error

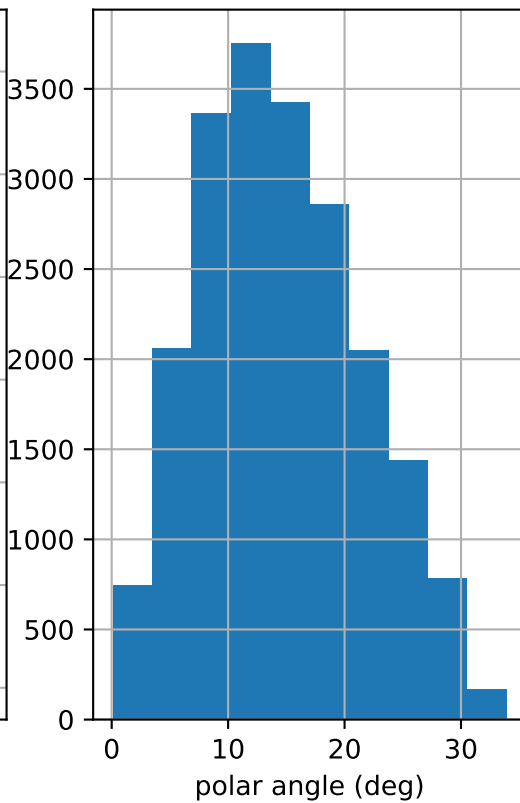
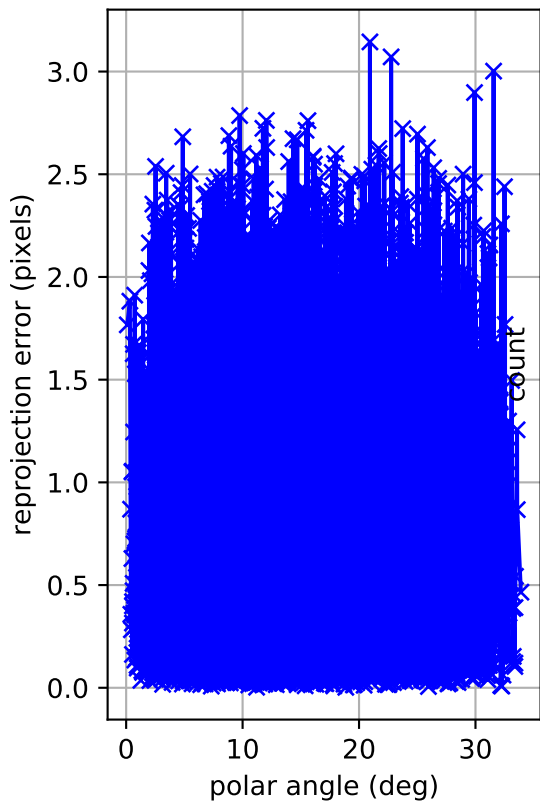




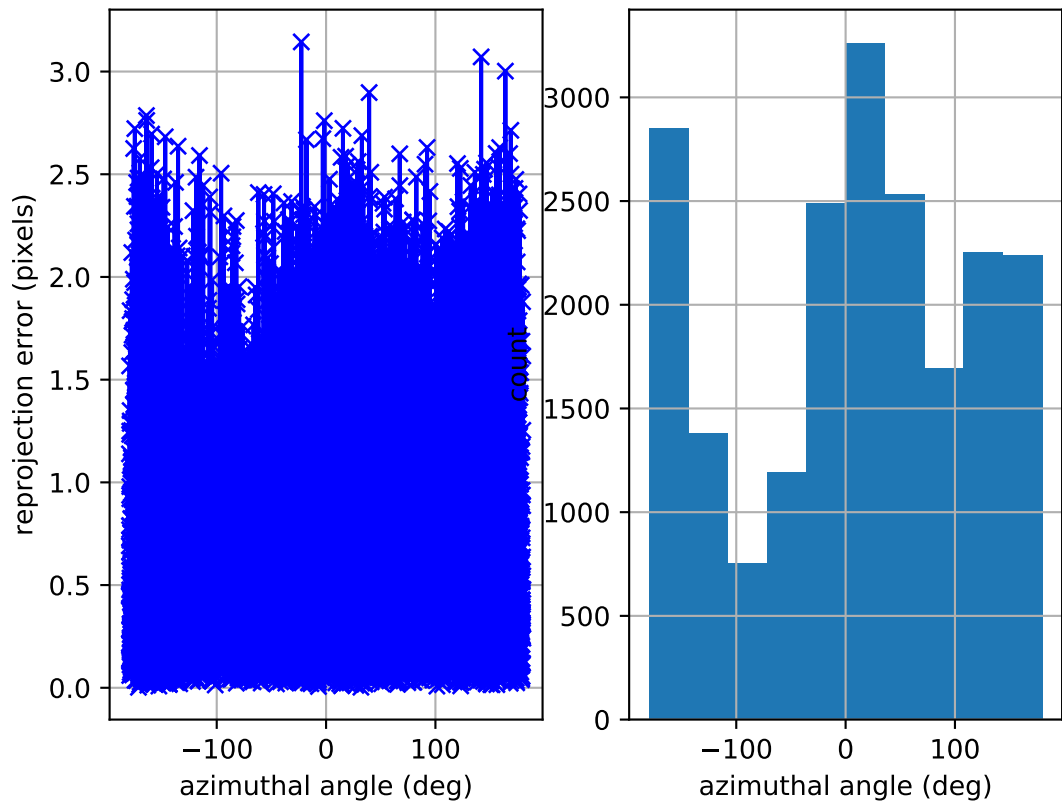
# cam3: reprojection errors



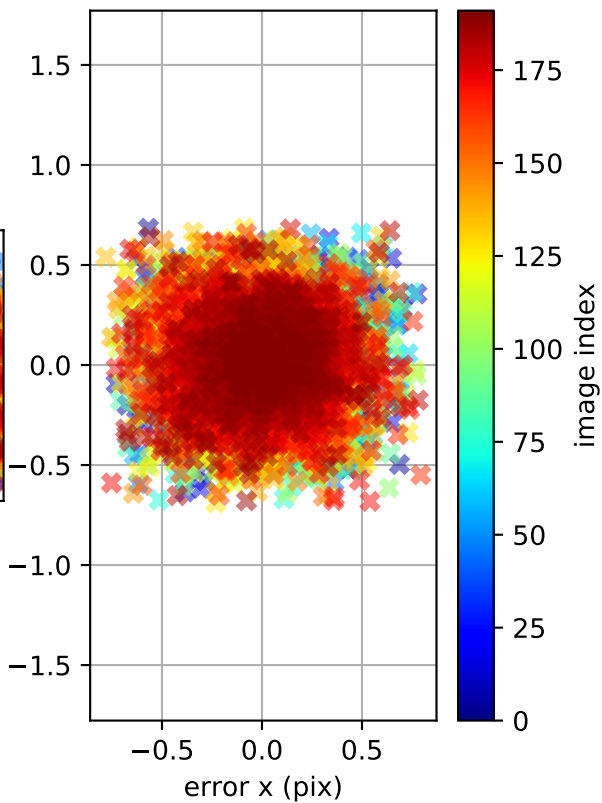
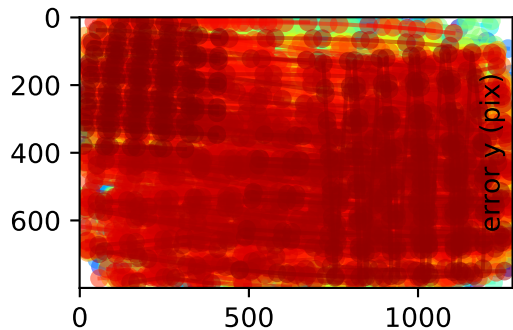
cam4: polar error



cam4: azimuthal error



# cam4: reprojection errors



# Location of removed outlier corners

