

## Calibration results

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### Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04704677 0.08206422 0.00012868 -0.00203682] +- [0.00104929 0.00230174 0.00008514 0.00005452]  
projection: [1032.42443788 1030.94699971 631.20230459 363.30264672] +- [0.15184661 0.16391565 0.00543742 0.12990125]

reprojection error: [0.000152, -0.000079] +- [0.475385, 0.372763]

cam1 (/prophesee/right/events):

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

distortion: [-0.0520274 0.08231713 0.00114129 -0.00093401] +- [0.00105752 0.00235277 0.00008276 0.00005447]  
projection: [1030.97096077 1029.9274685 631.62767462 365.73297913] +- [0.15649392 0.16947158 0.0060826 0.11728547]

reprojection error: [0.000160, -0.000106] +- [0.489382, 0.390367]

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

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

distortion: [-0.3928916 0.15627229 -0.00035599 0.00065398] +- [0.00051694 0.00086843 0.0000579 0.00003463]  
projection: [1059.1122614 1058.18378839 673.69057096 336.28991787] +- [0.14382279 0.14929563 0.00667382 0.23165567]

reprojection error: [0.000221, -0.000183] +- [0.297687, 0.189908]

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

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

distortion: [-0.39072977 0.15026993 -0.00045358 0.00130342] +- [0.00045152 0.00068581 0.00005493 0.00003448]  
projection: [1053.76602026 1053.24912424 670.58820826 328.54266761] +- [0.14268073 0.15004579 0.01842546 0.22054442]

reprojection error: [0.000231, -0.000185] +- [0.292417, 0.186634]

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

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

distortion: [-0.41510203 0.18645652 0.00012393 0.00001056] +- [0.00080481 0.00198968 0.00005796 0.00003925]  
projection: [1265.34201581 1263.72569643 652.56058684 366.52401563] +- [0.14113221 0.14801874 0.00679763 0.09832865]

reprojection error: [0.000007, -0.000109] +- [0.243283, 0.200568]

baseline T\_1\_0:

q: [-0.00072746 0.00179696 -0.00026868 0.99999808] +- [0.00013397 0.00004865 0.00004286]

t: [-0.12009635 0.00097434 -0.00044348] +- [0.00003352 0.00003318 0.00014624]

baseline T\_2\_1:

q: [-0.00002053 -0.00158083 -0.0047675 0.99998739] +- [0.00027949 0.00004379 0.00003943]

t: [0.12041573 0.06924164 0.00535911] +- [0.00003073 0.00003156 0.00014402]

baseline T\_3\_2:

q: [-0.00002901 -0.00122951 0.00033736 0.99999919] +- [0.00031436 0.00004511 0.00003362]

t: [-0.11996595 -0.00008708 0.00096004] +- [0.00002791 0.00002828 0.00013639]

baseline T\_4\_3:

q: [0.00237256 0.00379689 0.00024344 0.99998995] +- [0.00025856 0.00004217 0.00003339]

t: [0.08859853 0.00623647 0.00260523] +- [0.00002561 0.00002622 0.00012598]

Target configuration

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Type: aprilgrid

Tags:

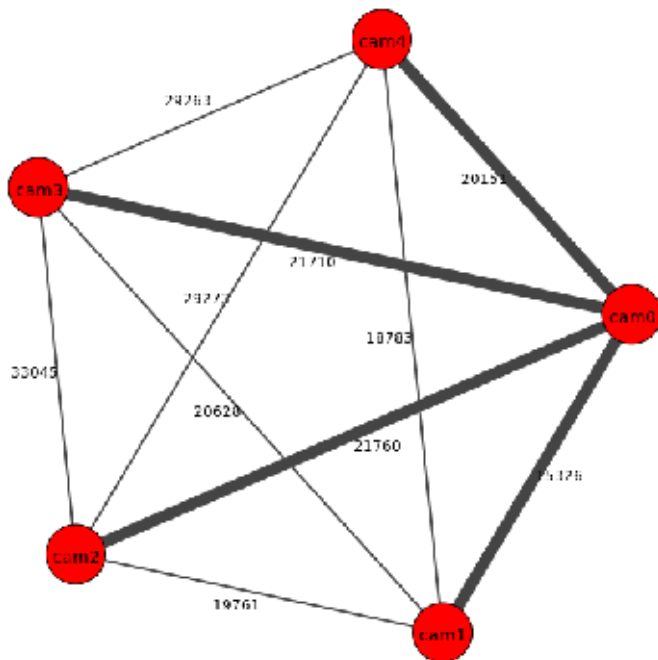
Rows: 5

Cols: 7

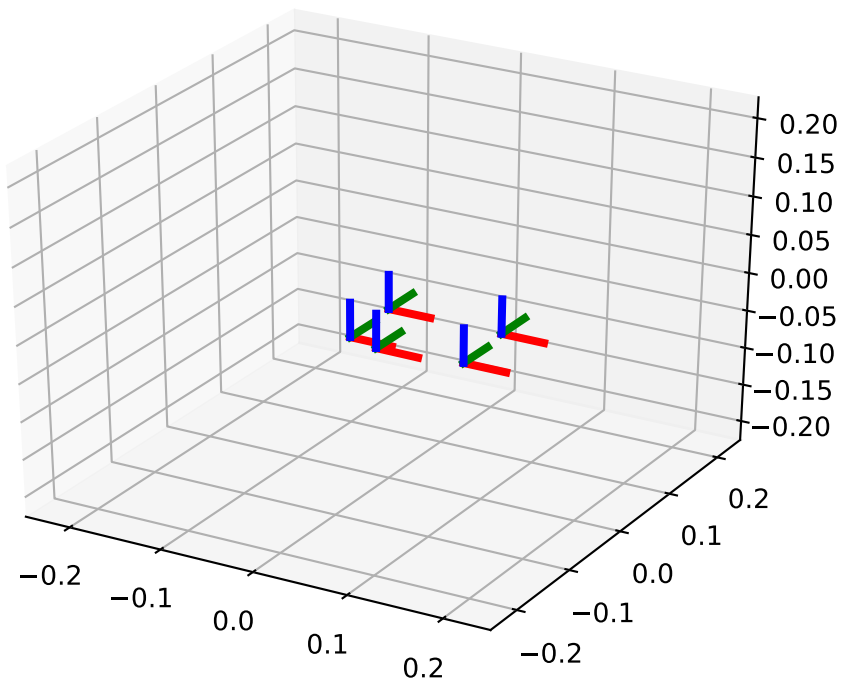
Size: 0.04 [m]

Spacing 0.01 [m]

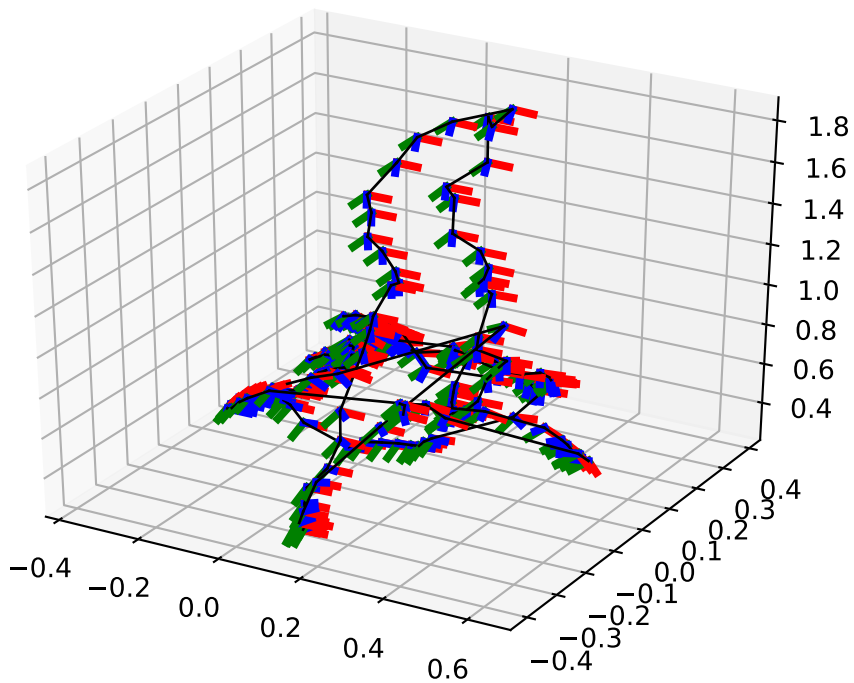
Inter-camera observations graph (edge weight=#mutual obs.)



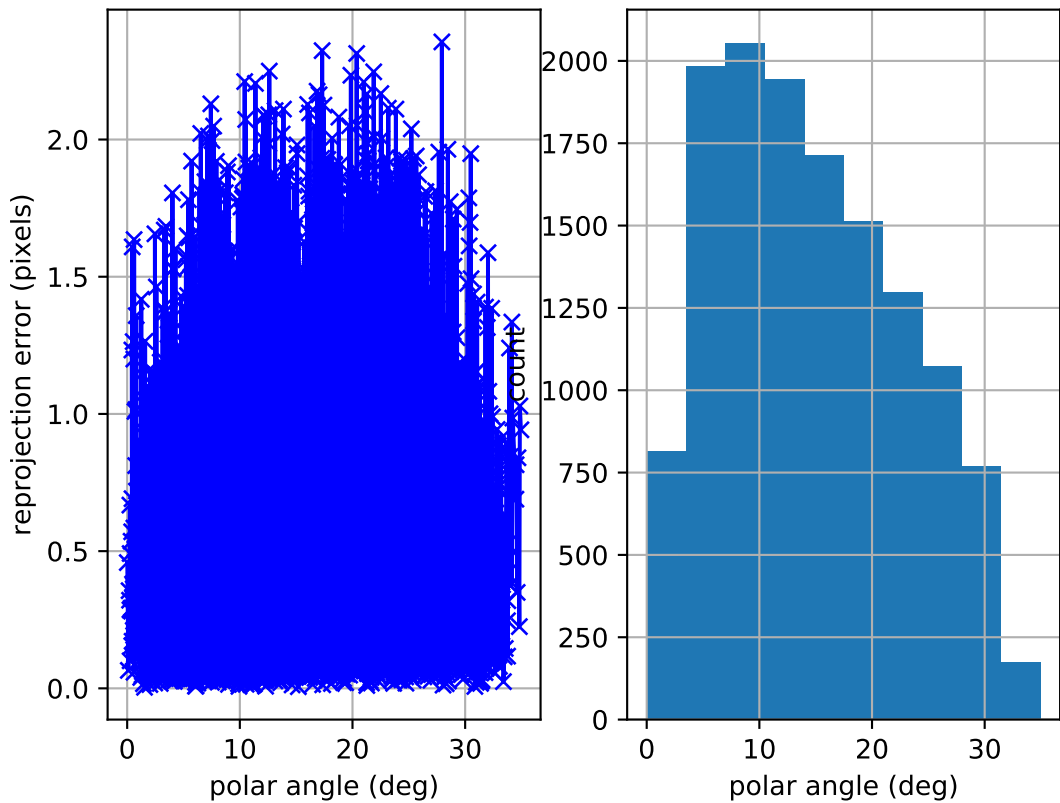
camera system



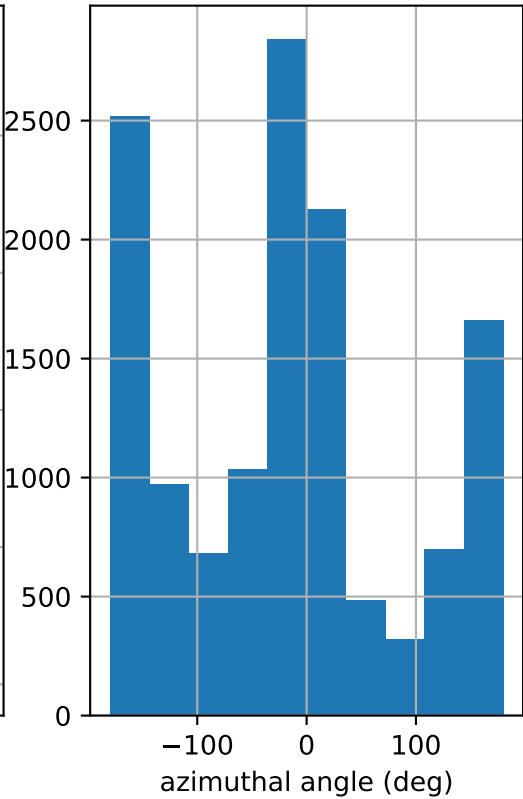
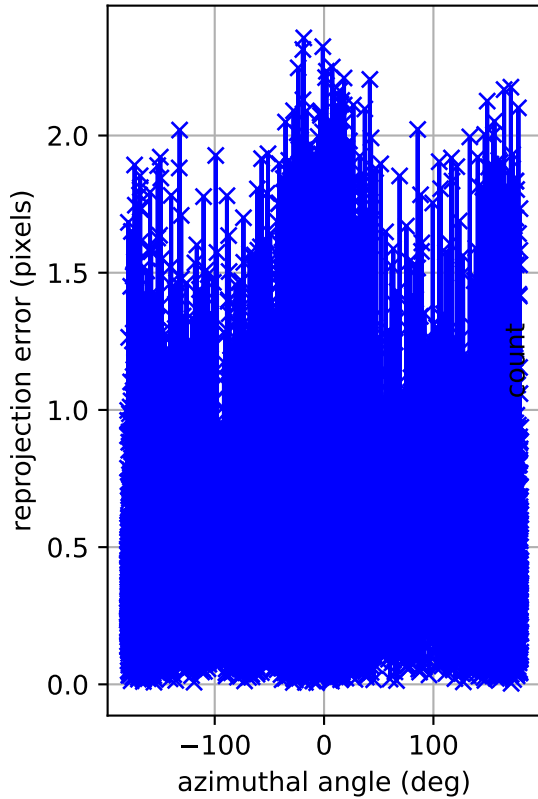
cam0: estimated poses



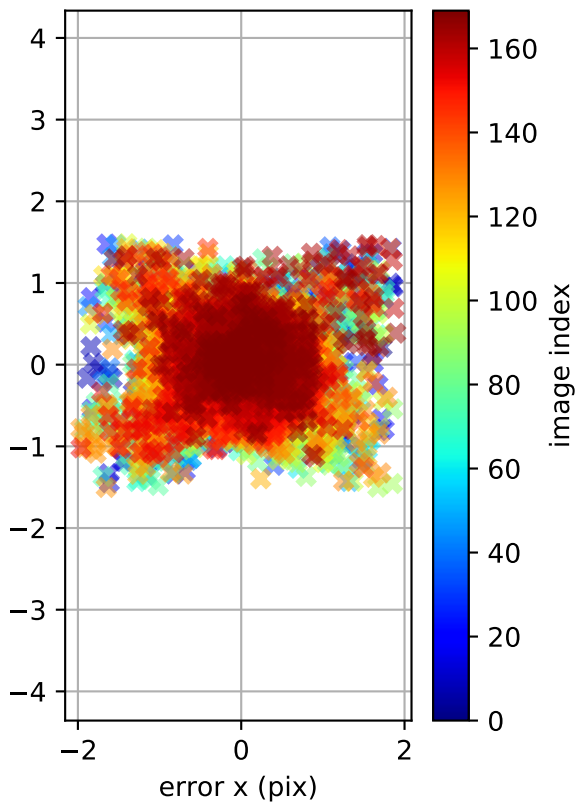
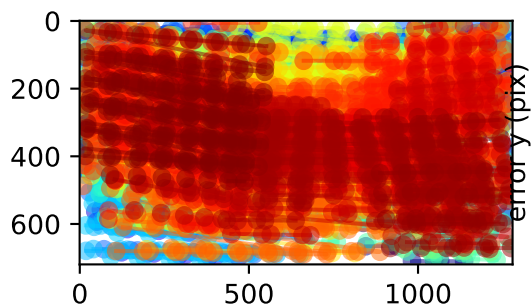
cam0: polar error



cam0: azimuthal error

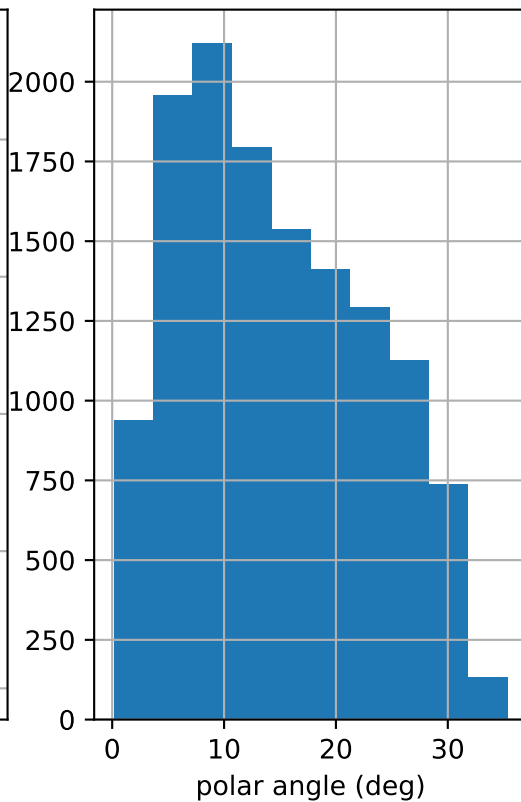
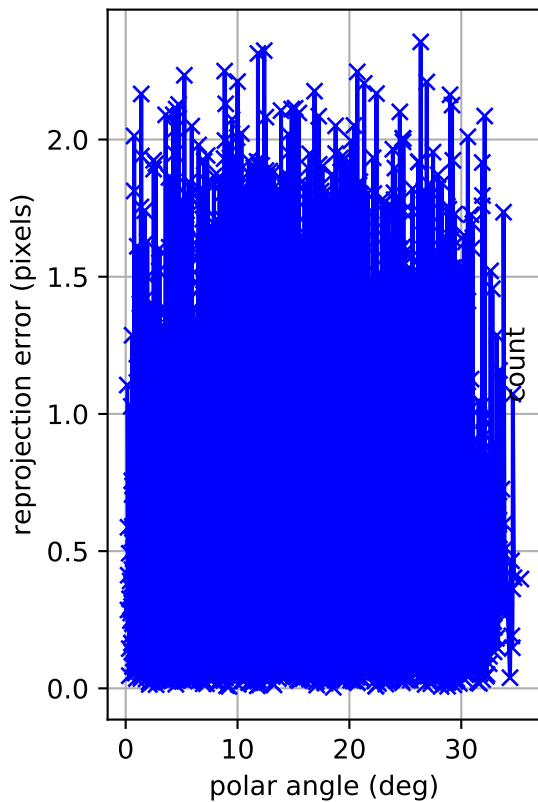


# cam0: reprojection errors

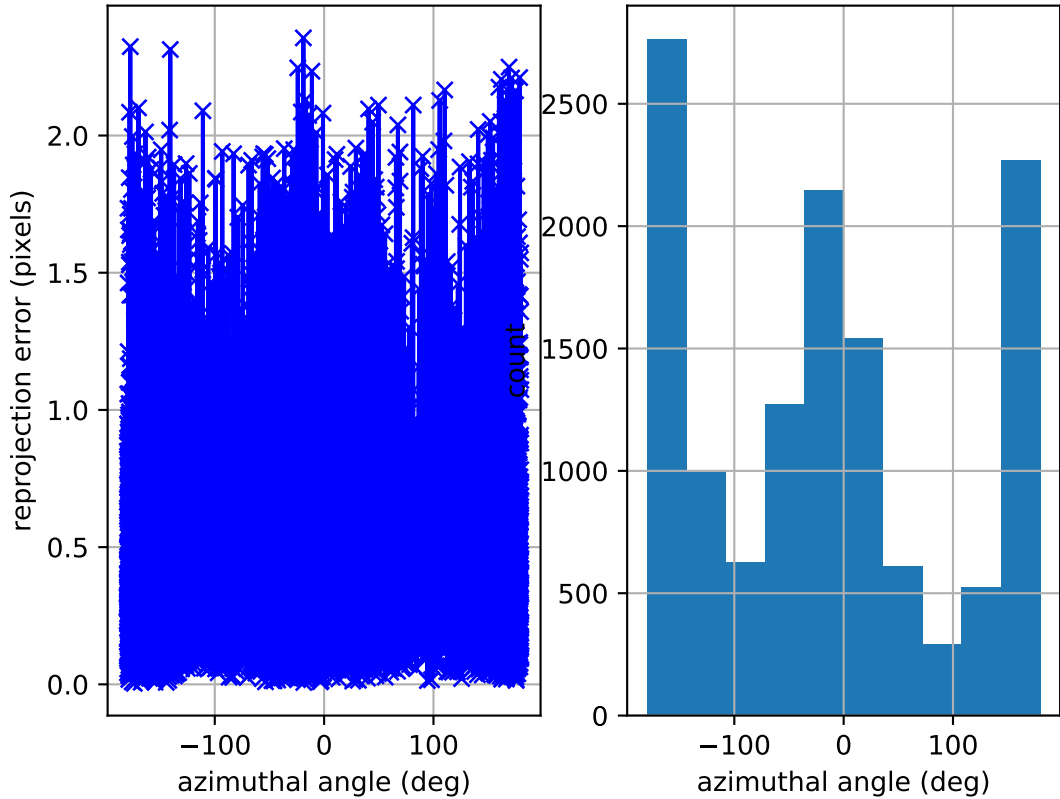




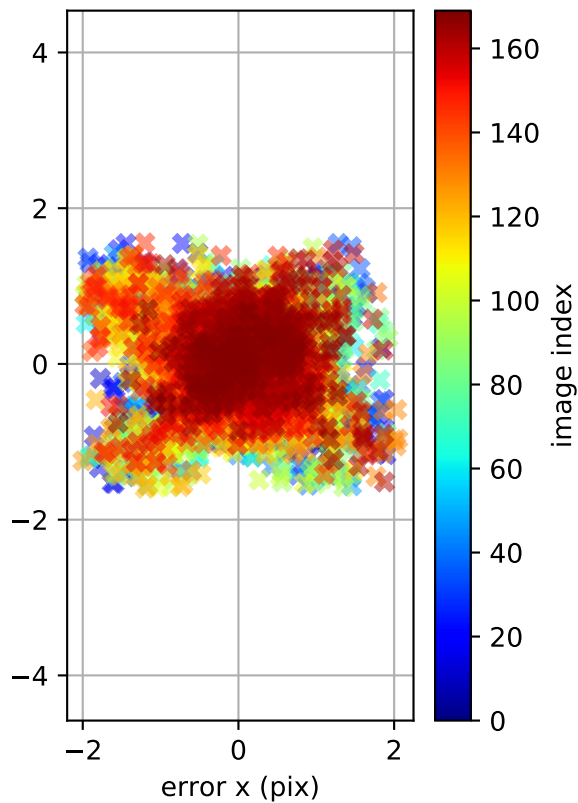
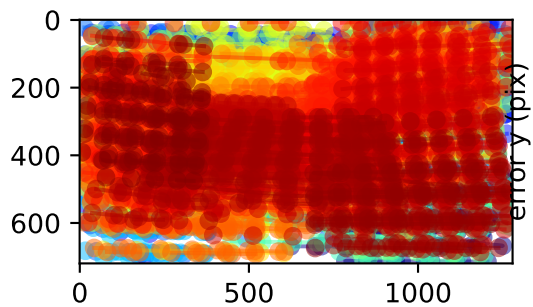
cam1: polar error



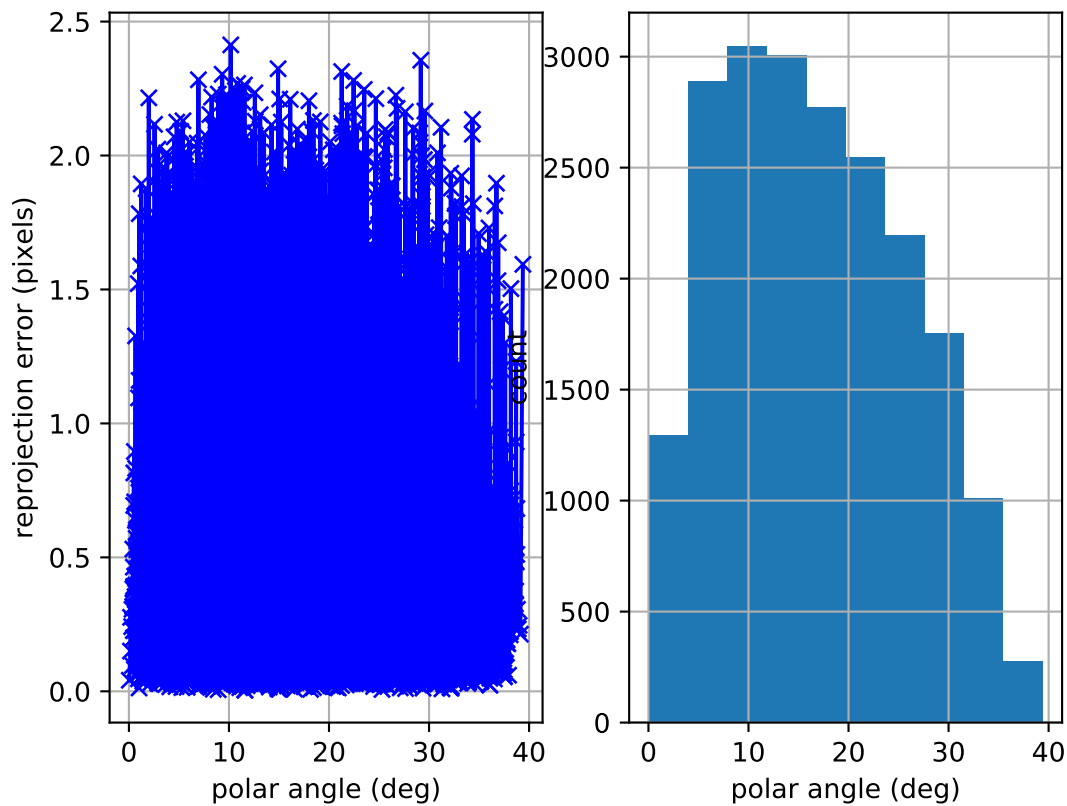
cam1: azimuthal error



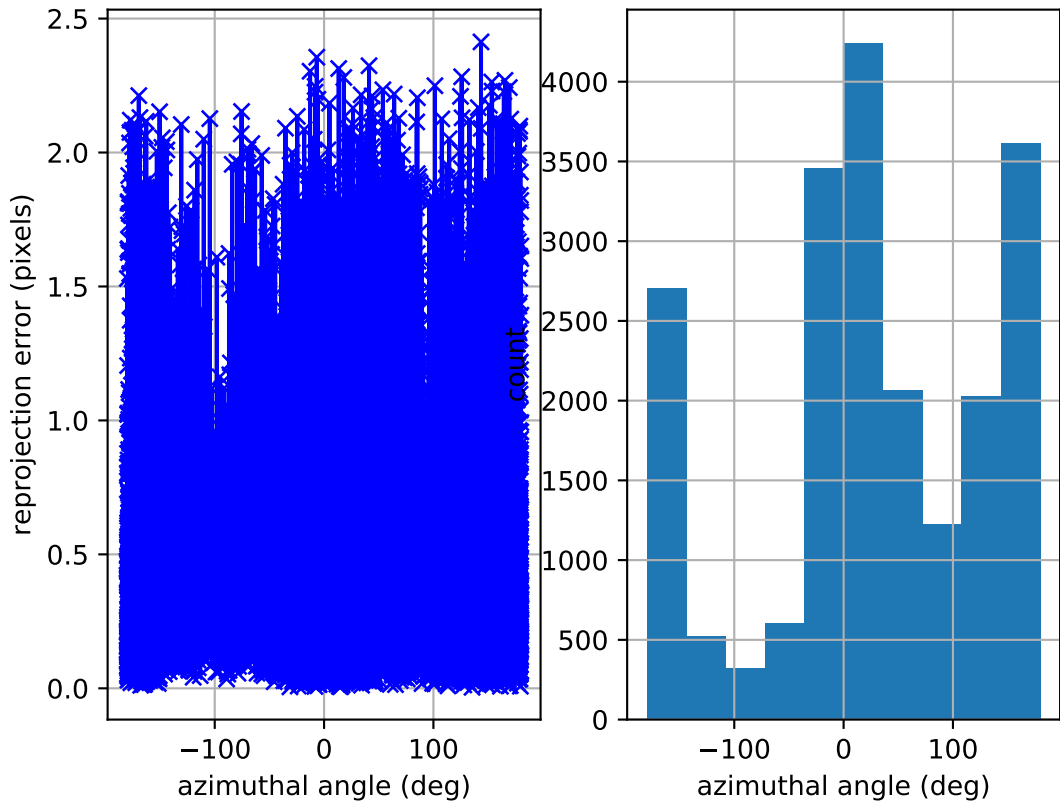
# cam1: reprojection errors



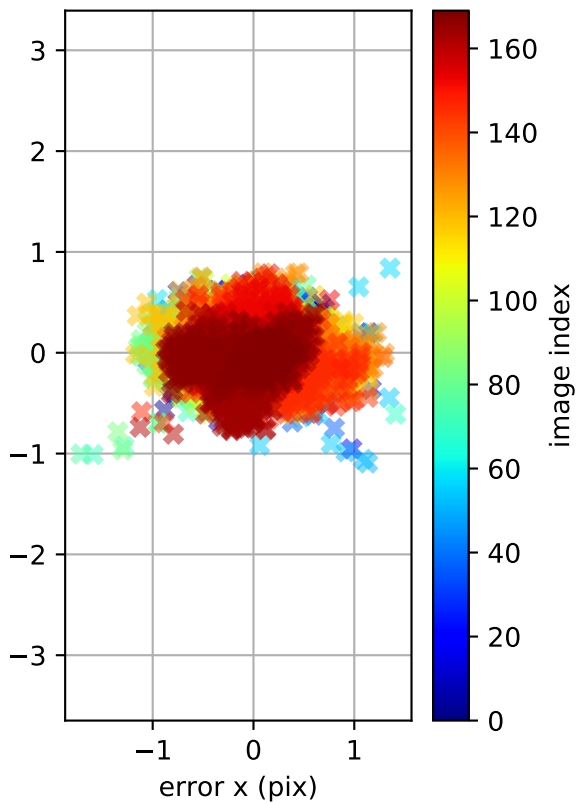
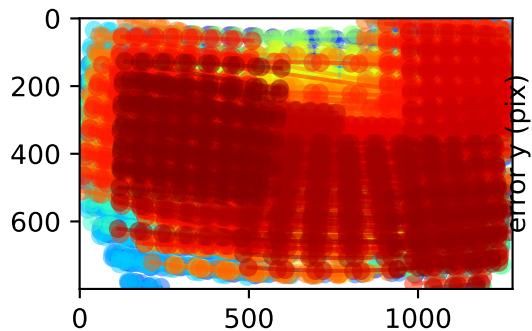
cam2: polar error



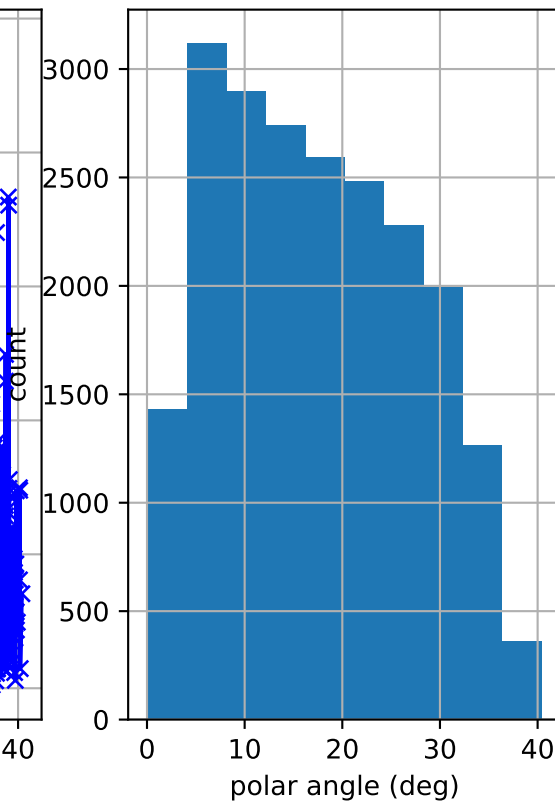
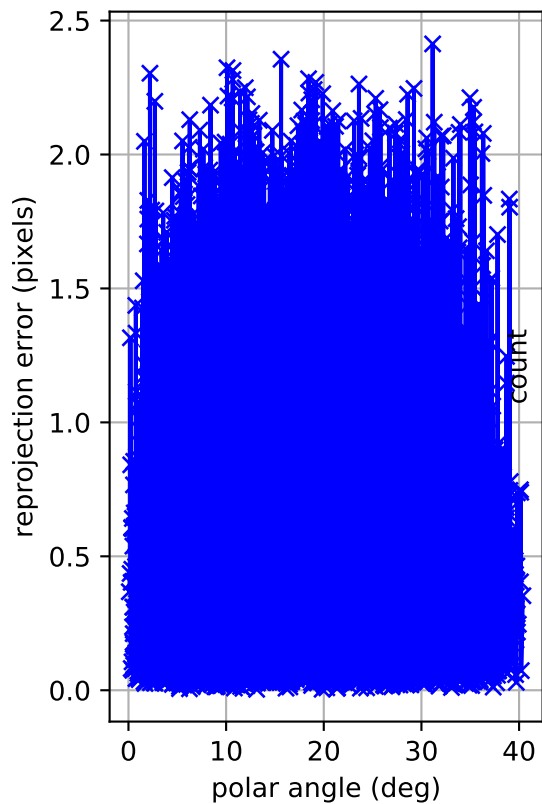
cam2: azimuthal error



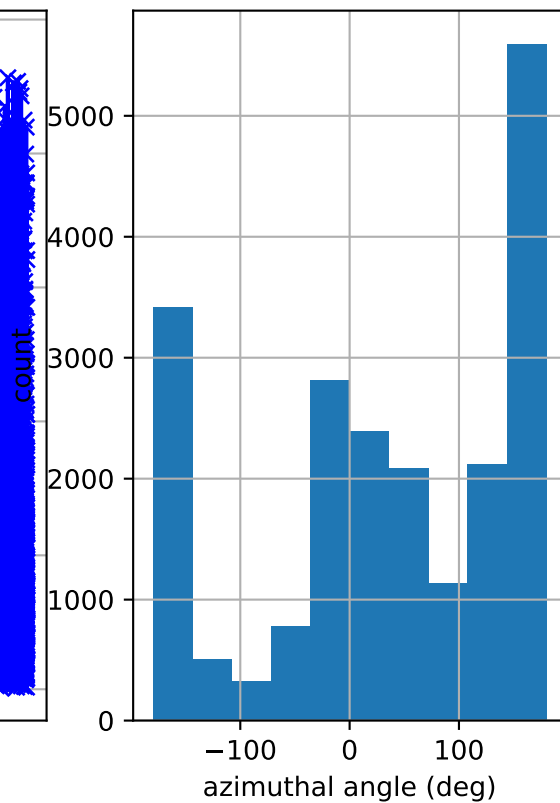
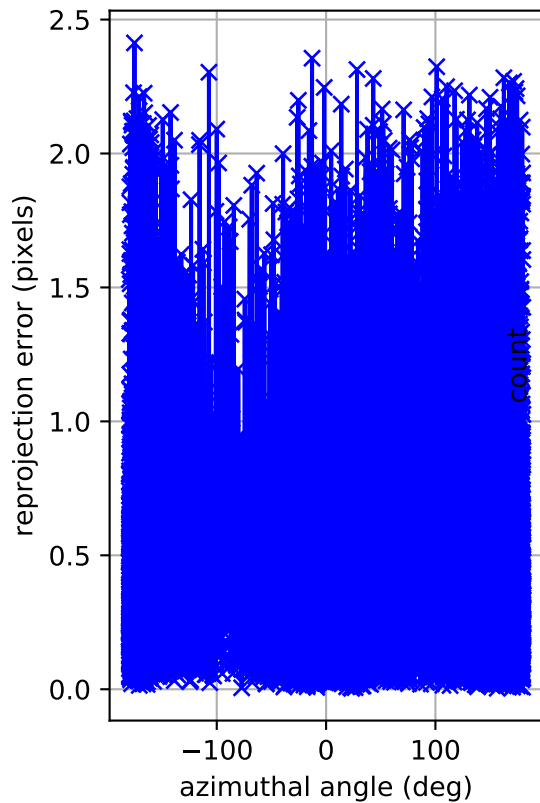
## cam2: reprojection errors



cam3: polar error

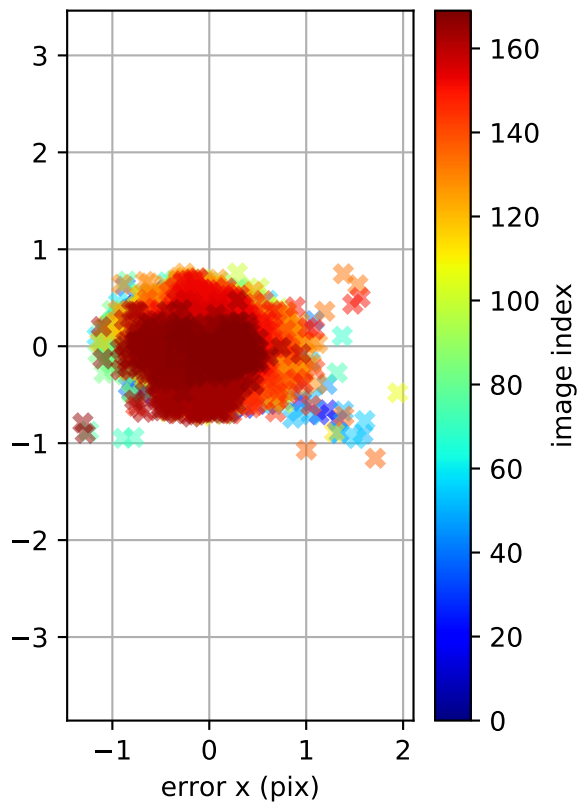
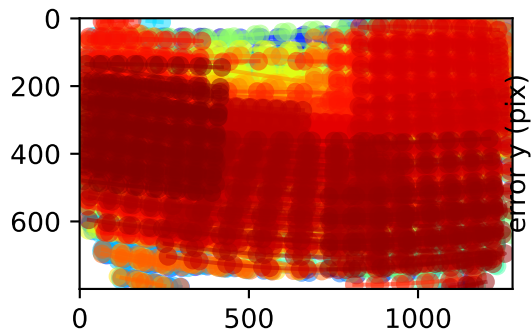


cam3: azimuthal error

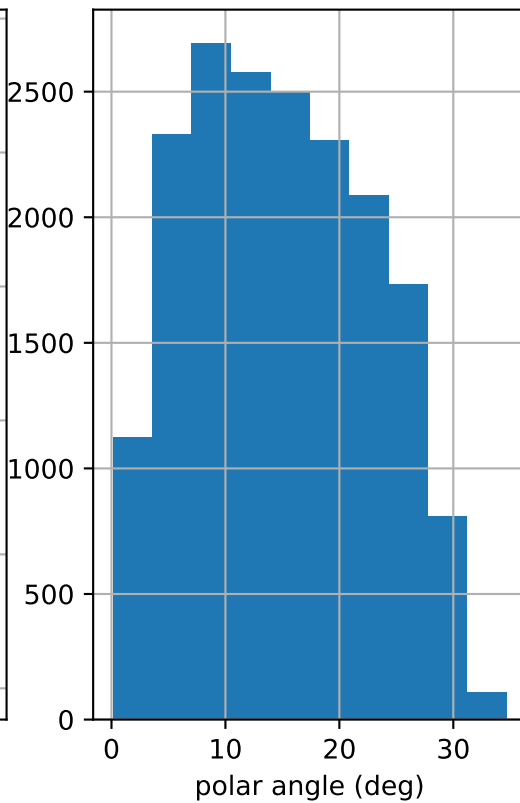
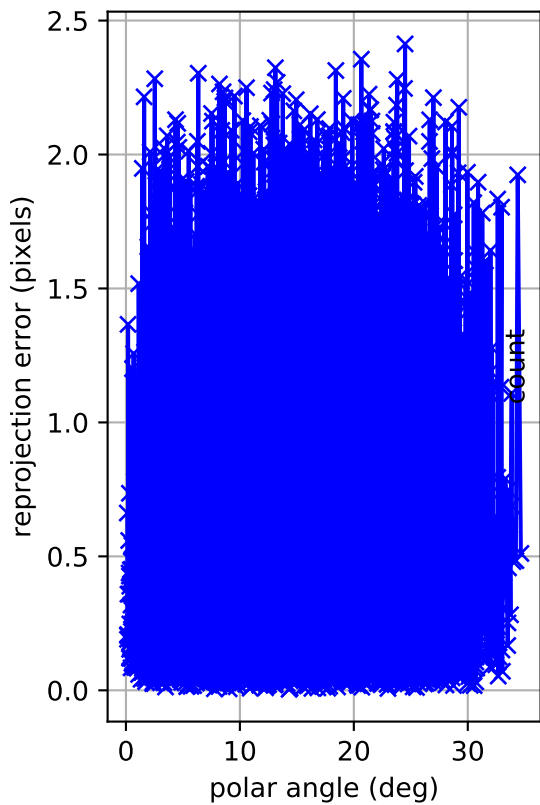




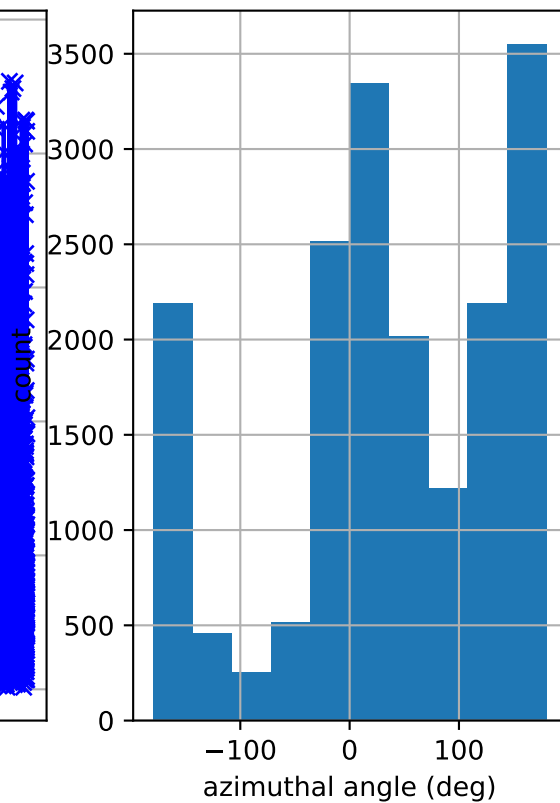
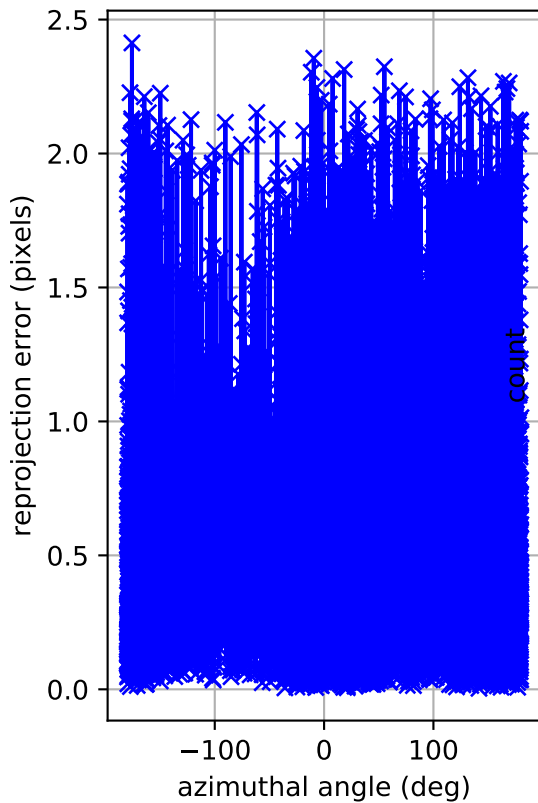
# cam3: reprojection errors



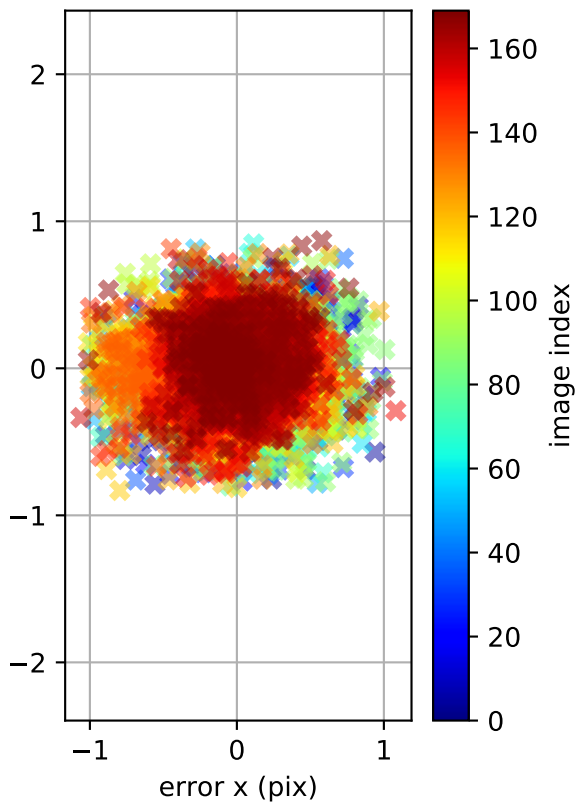
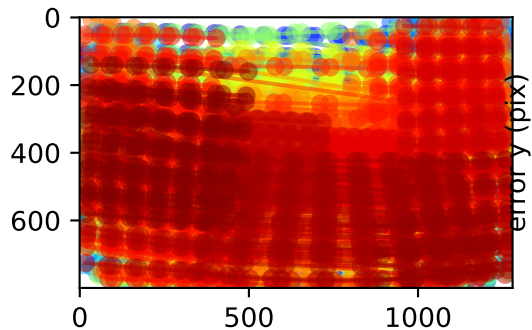
cam4: polar error



cam4: azimuthal error



# cam4: reprojection errors



# Location of removed outlier corners

