

## Calibration results

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### Camera-system parameters:

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

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

distortion: [-0.04165452 0.07621236 0.00058955 -0.00151461] +- [0.00088379 0.00186162 0.00009892 0.00007421]

projection: [1037.24321134 1036.88138558 633.36297798 365.19754371] +- [0.07274414 0.07755088 0.03464064 0.20140487]

reprojection error: [0.000108, 0.000012] +- [0.314298, 0.290034]

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

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

distortion: [-0.04666126 0.07605365 0.00169855 -0.00024074] +- [0.0009685 0.00212168 0.00009592 0.00007933]

projection: [1036.16175276 1036.18559699 635.59559667 368.07333459] +- [0.09231352 0.08537862 0.02161896 0.15841178]

reprojection error: [0.000132, -0.000034] +- [0.350758, 0.328559]

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

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

distortion: [-0.39457437 0.15746355 -0.00002763 0.00063972] +- [0.00057441 0.00096123 0.00006754 0.00004775]

projection: [1063.06953713 1062.82826405 673.78347956 337.25106623] +- [0.14205482 0.14416943 0.02661696 0.19402032]

reprojection error: [0.000118, -0.000179] +- [0.188381, 0.150298]

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

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

distortion: [-0.39442492 0.15322736 -0.00012977 0.00123765] +- [0.00050353 0.00076911 0.00006537 0.0000524 ]

projection: [1058.34730329 1058.63396112 671.45531236 329.15566514] +- [0.13483184 0.14118983 0.03556587 0.18187633]

reprojection error: [0.000126, -0.000126] +- [0.207981, 0.162927]

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

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

distortion: [-0.41549554 0.18349788 0.00013463 0.00004864] +- [0.0007306 0.00168199 0.00006999 0.00005085]

projection: [1270.65972499 1270.34115238 653.48454335 369.19216467] +- [0.09419692 0.09555841 0.01707815 0.09074577]

reprojection error: [-0.000058, 0.000009] +- [0.170109, 0.165193]

#### baseline T\_1\_0:

q: [-0.00112908 0.00232497 -0.0003736 0.99999659] +- [0.00030688 0.00007347 0.0000386 ]

t: [-0.12025072 0.00091967 -0.00031381] +- [0.00004845 0.00004544 0.00010098]

baseline T\_2\_1:

q: [-0.00064412 -0.00266381 -0.00513866 0.99998304] +- [0.00028506 0.00006148 0.00003651]

t: [0.12034698 0.06912689 0.00399358] +- [0.00004561 0.00004476 0.00014192]

baseline T\_3\_2:

q: [ 0.00052973 -0.00243622 0.00021776 0.99999687] +- [0.00027062 0.00006341 0.00003144]

t: [-0.12010729 -0.00000962 0.00149645] +- [0.00004164 0.00004004 0.00014923]

baseline T\_4\_3:

q: [0.00156362 0.00533756 0.00039152 0.99998446] +- [0.00021352 0.00005991 0.00003017]

t: [0.08884395 0.00615082 0.00324217] +- [0.00003822 0.00003813 0.00013013]

Target configuration

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Type: aprilgrid

Tags:

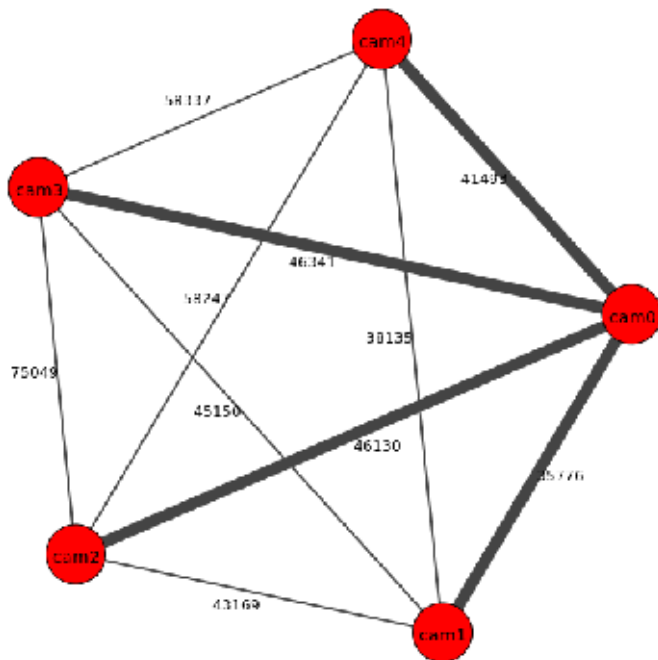
Rows: 5

Cols: 7

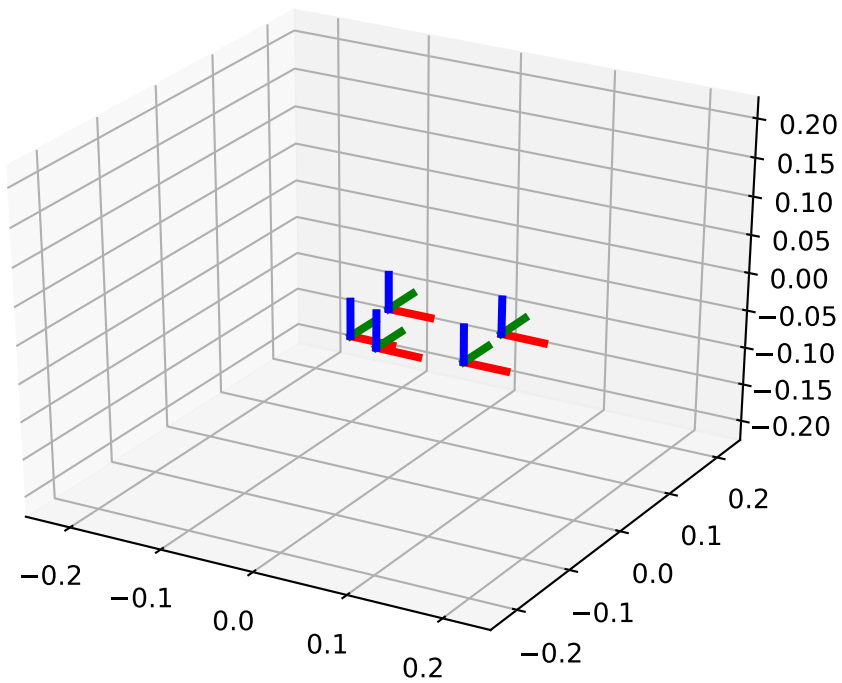
Size: 0.04 [m]

Spacing 0.01 [m]

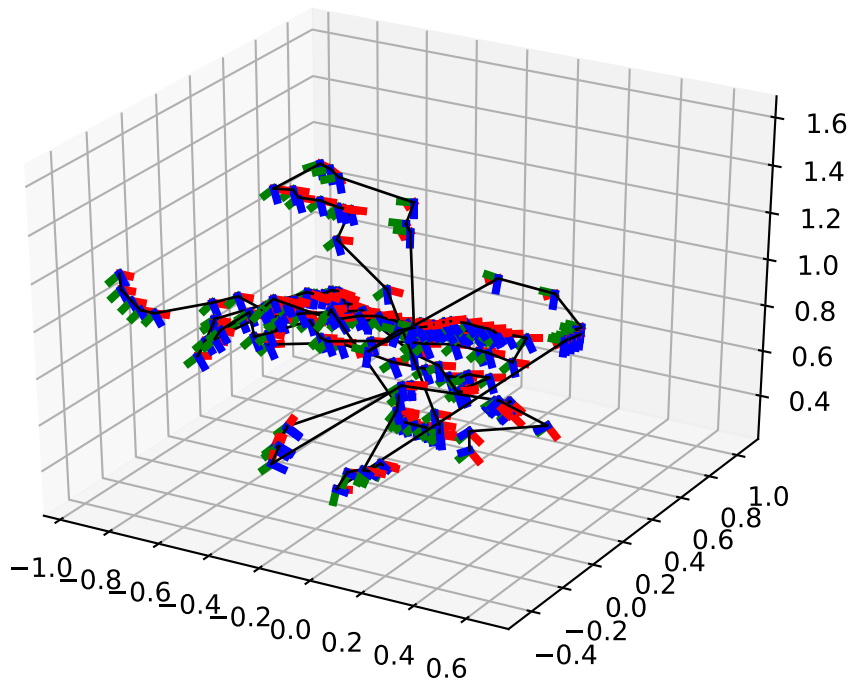
Inter-camera observations graph (edge weight=#mutual obs.)



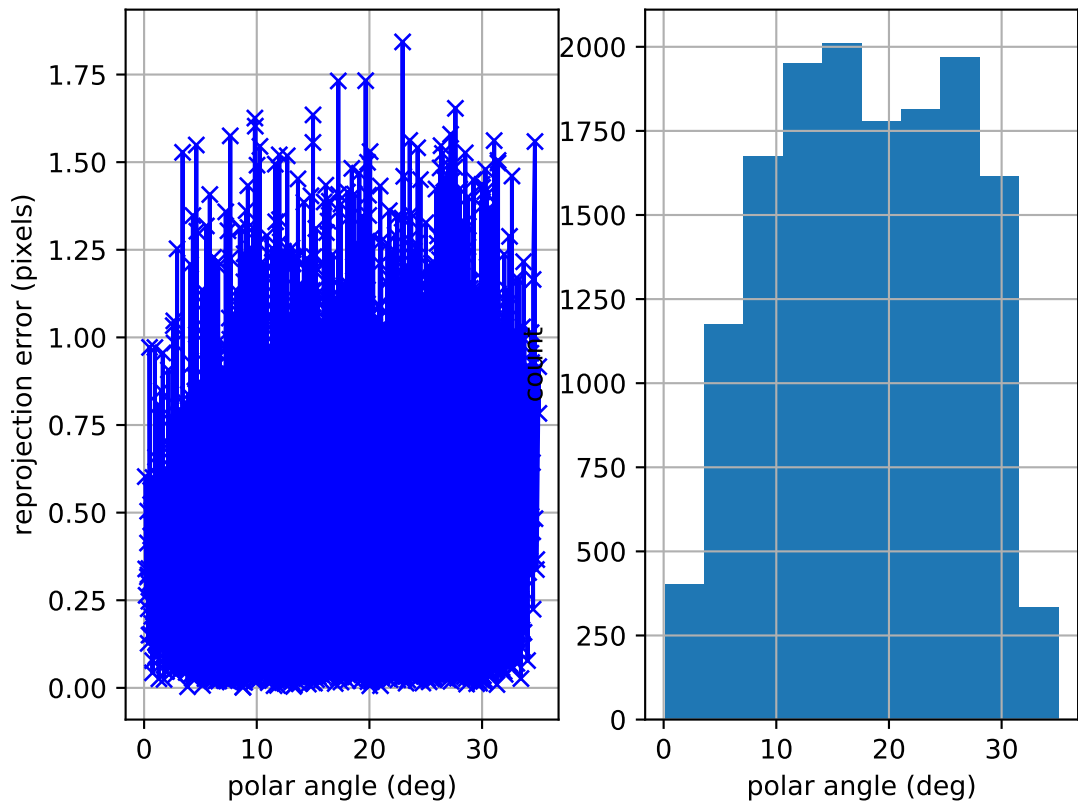
camera system



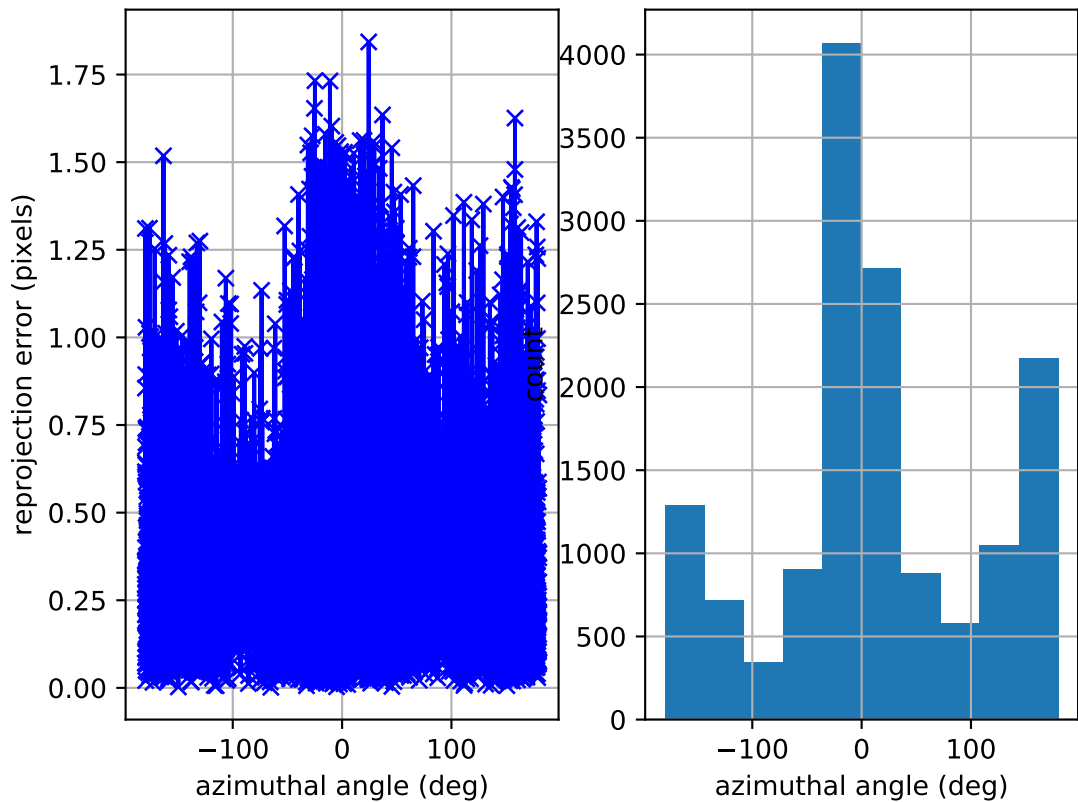
cam0: estimated poses



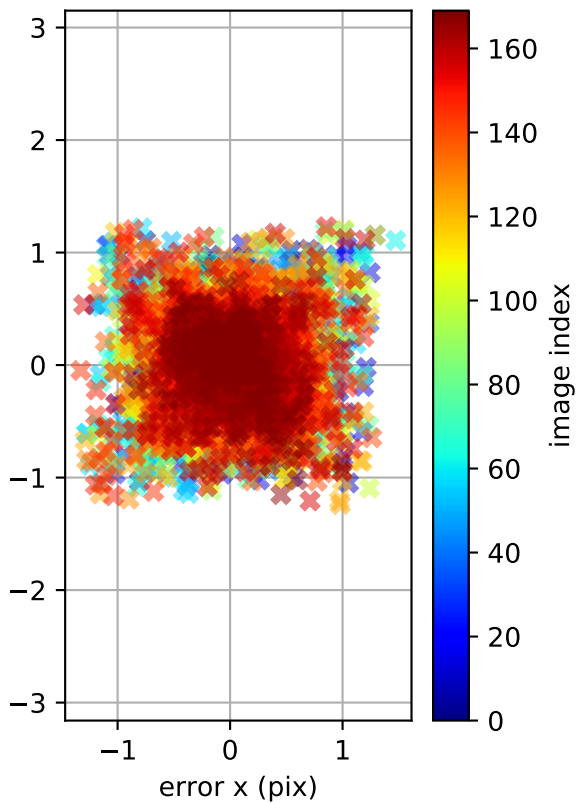
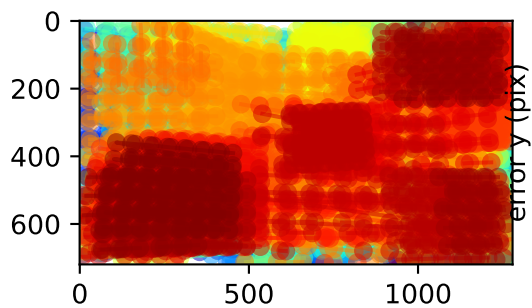
cam0: polar error



cam0: azimuthal error

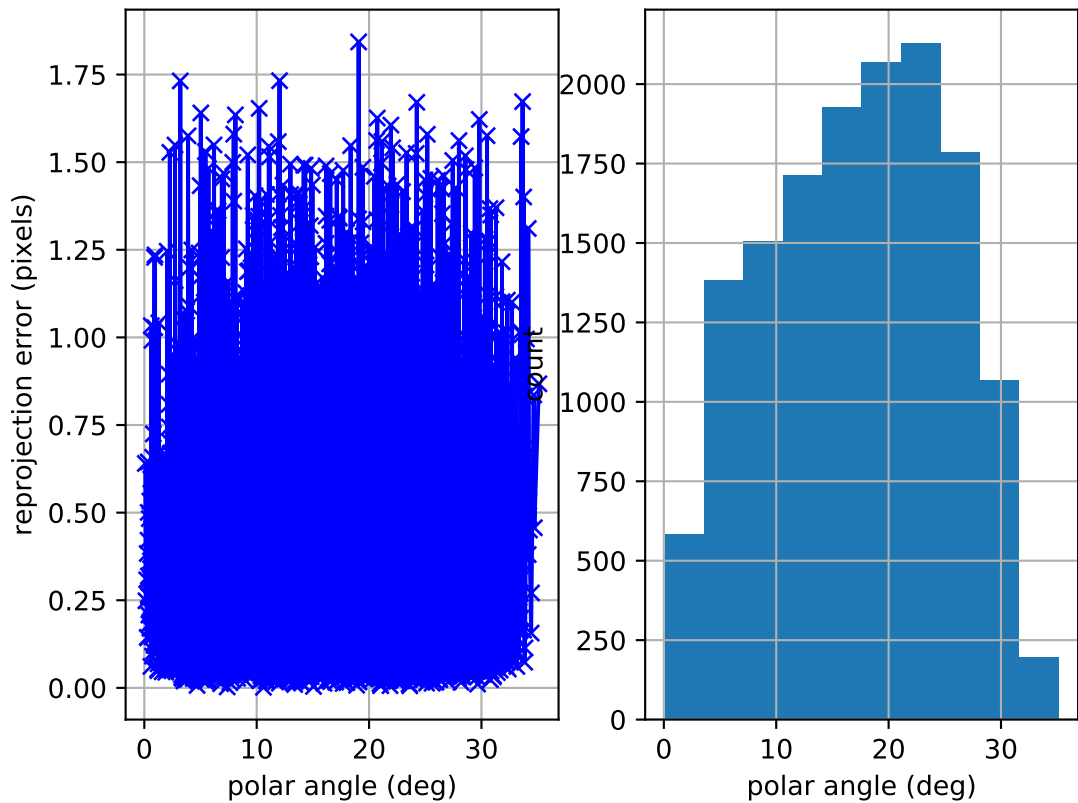


# cam0: reprojection errors

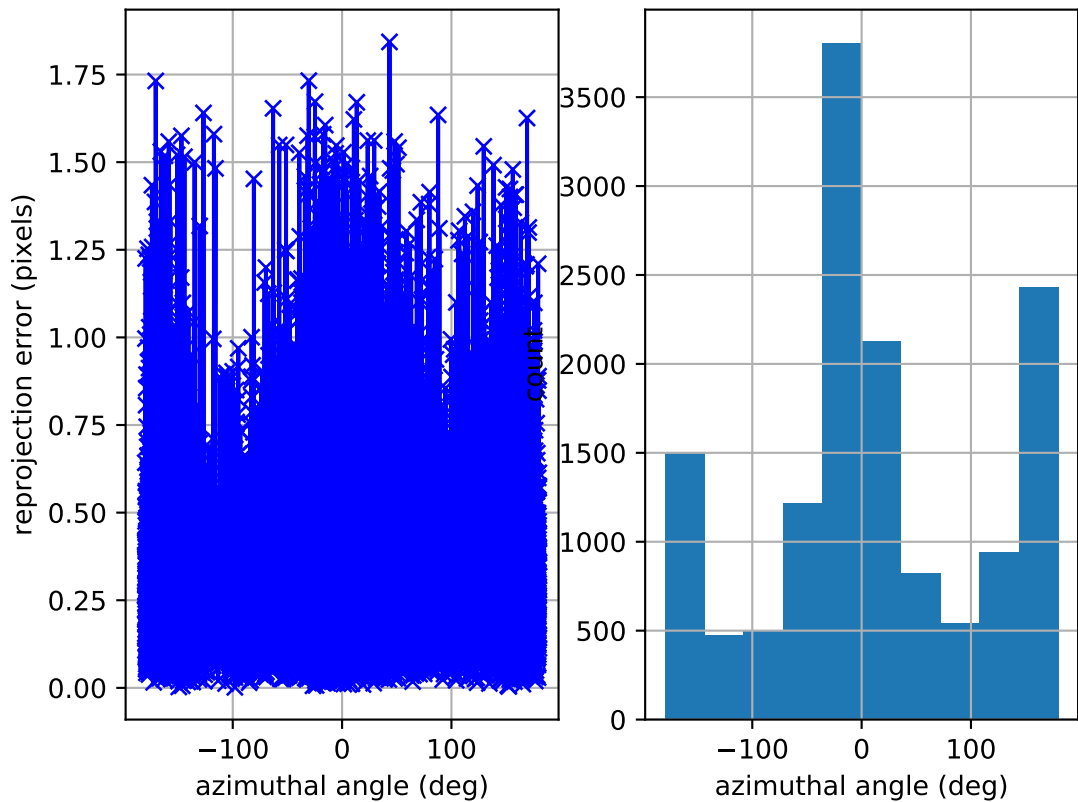




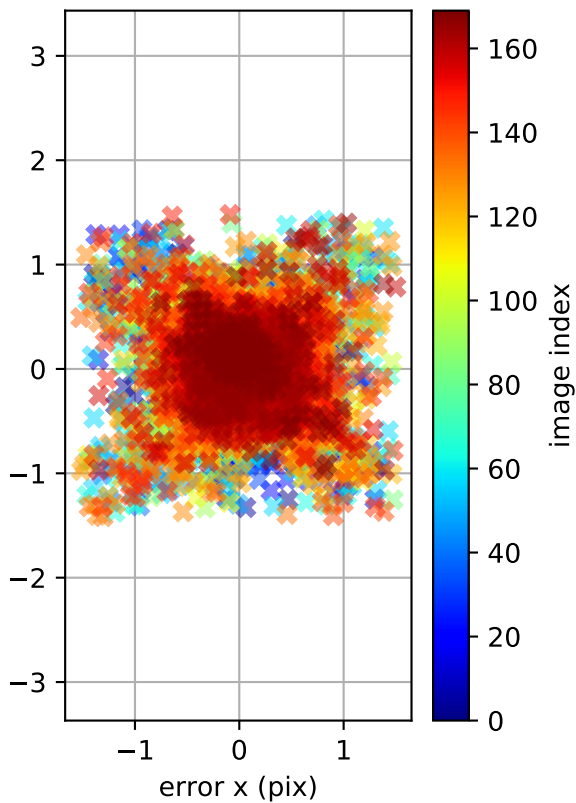
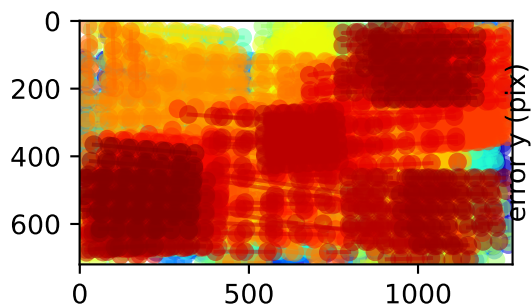
cam1: polar error



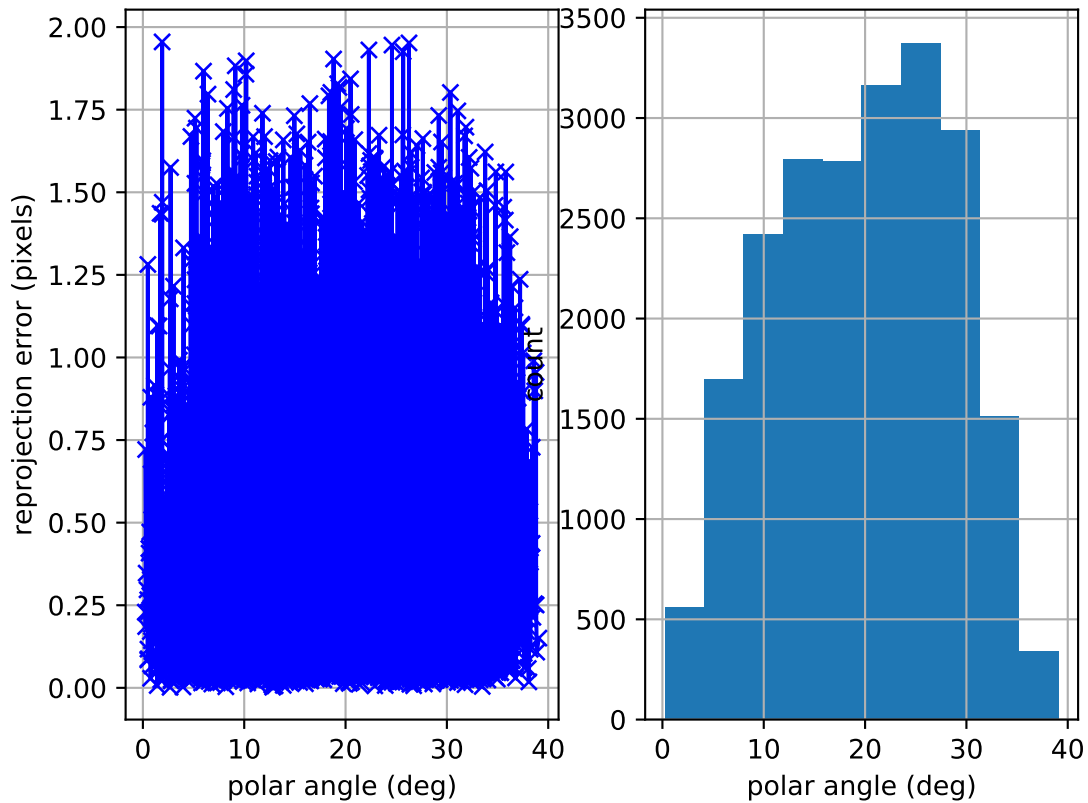
cam1: azimuthal error



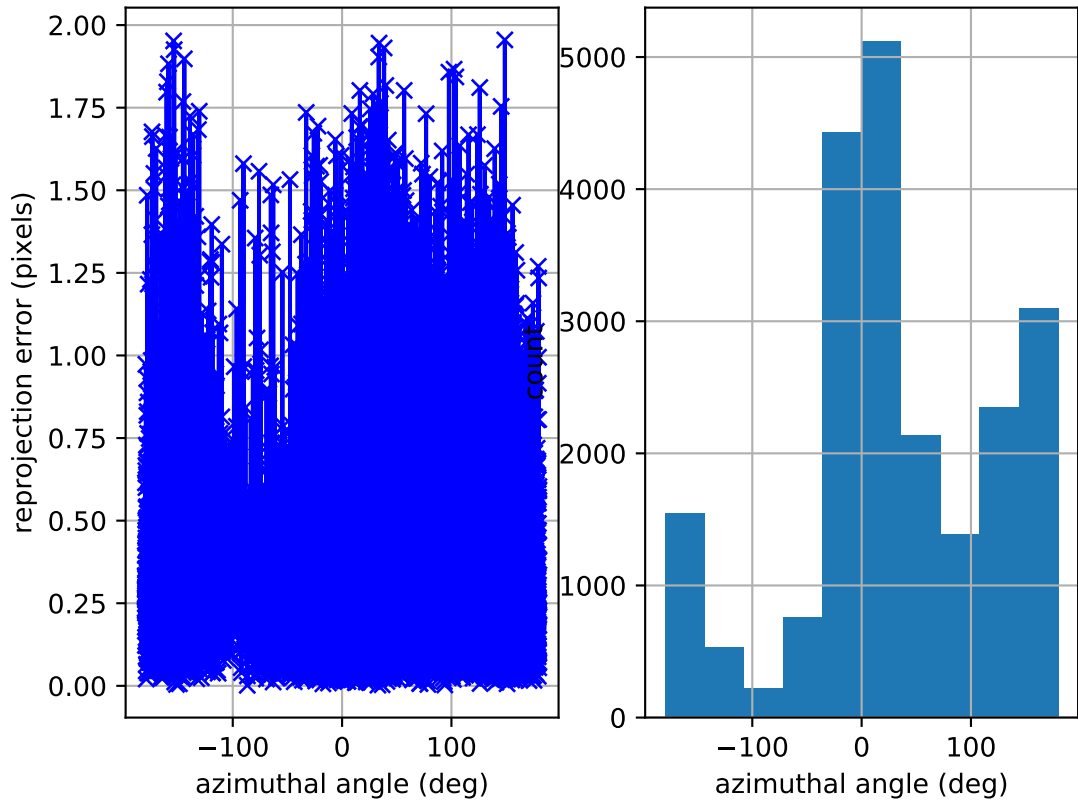
# cam1: reprojection errors



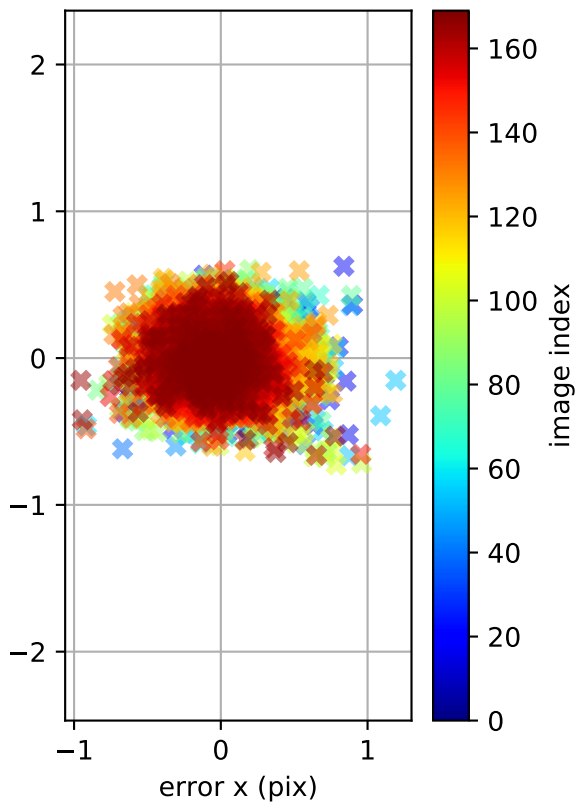
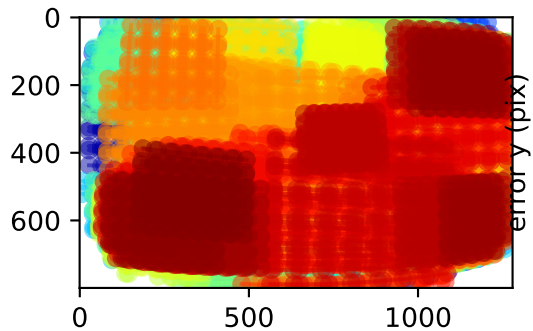
# cam2: polar error



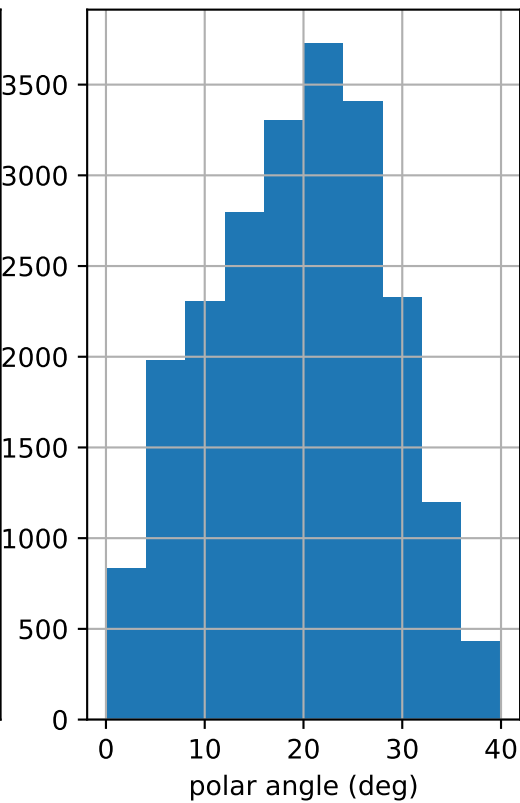
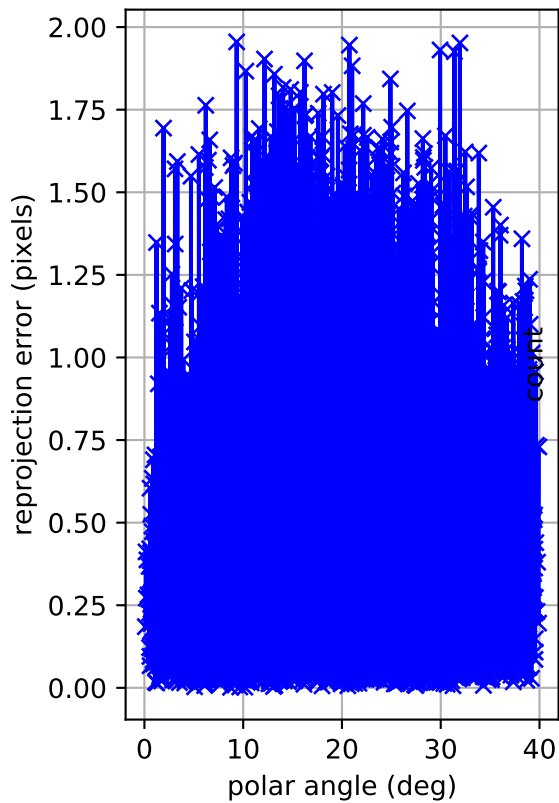
cam2: azimuthal error



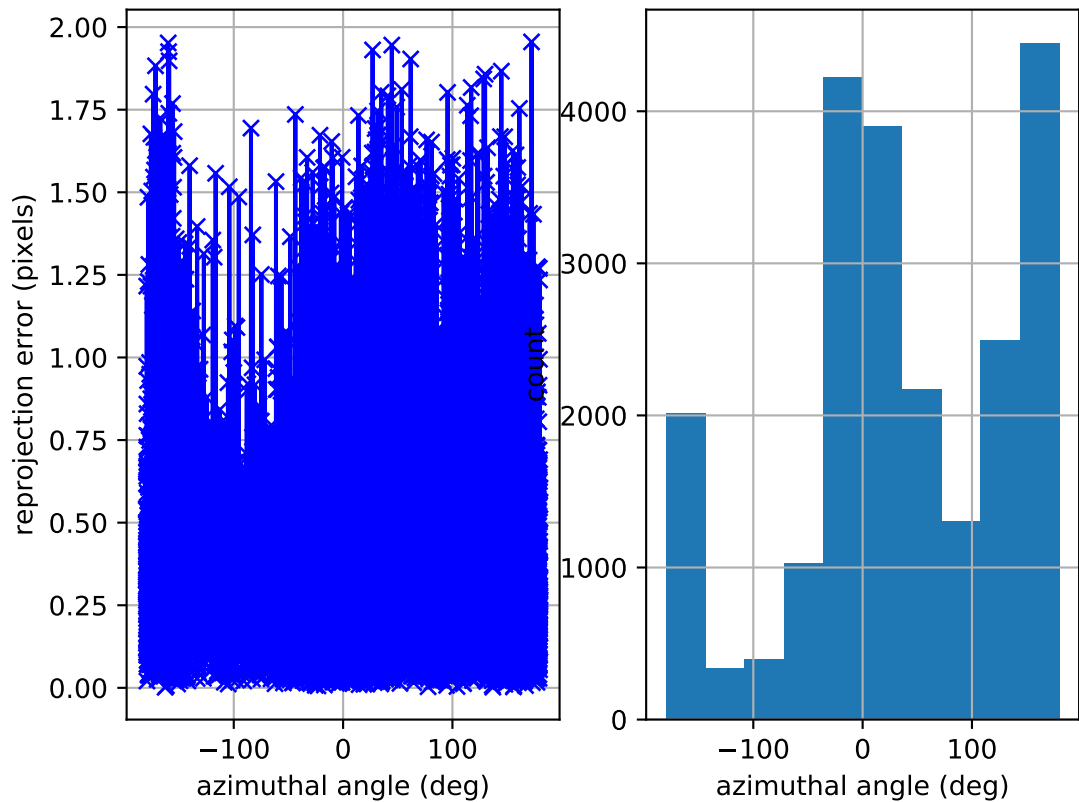
## cam2: reprojection errors



cam3: polar error

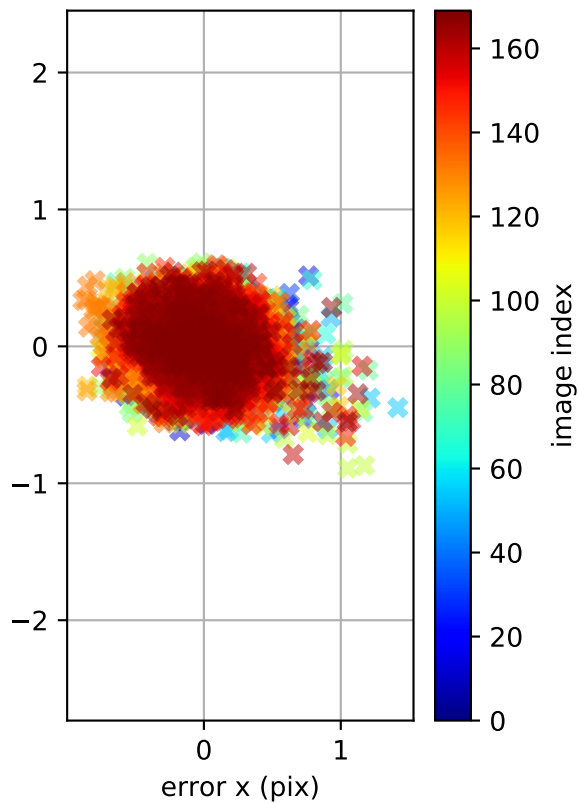
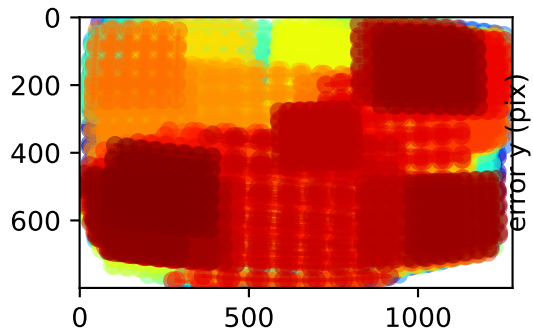


cam3: azimuthal error

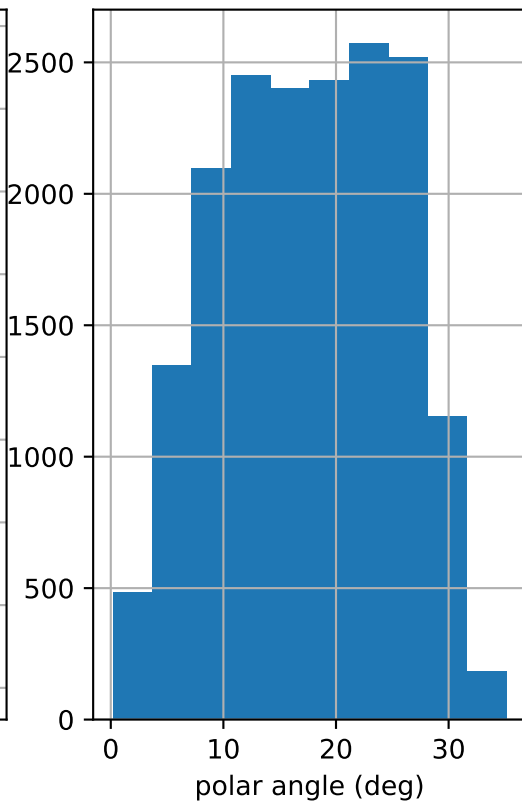
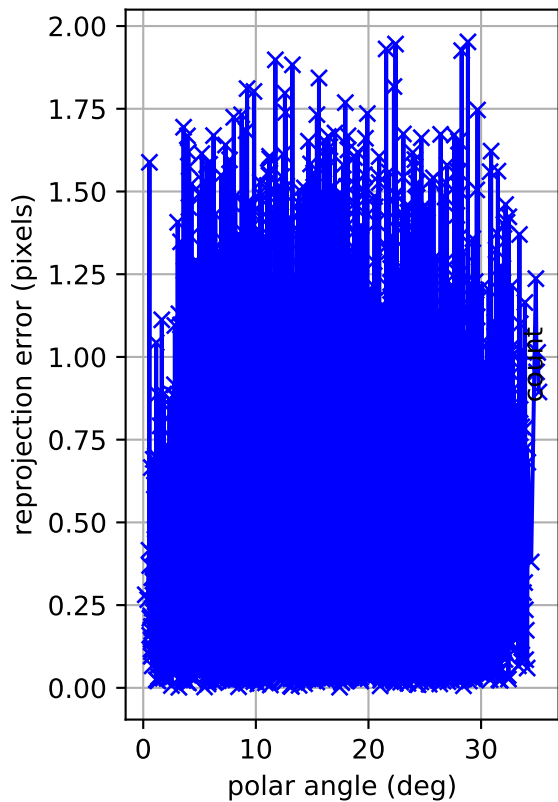




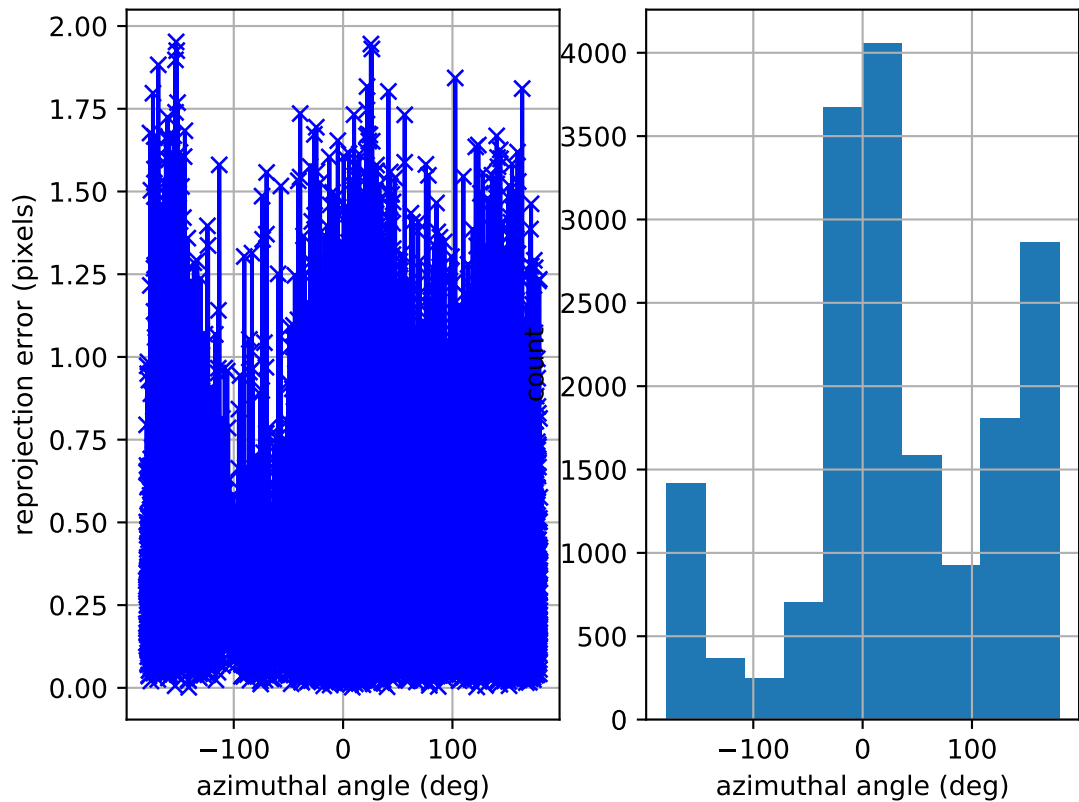
# cam3: reprojection errors



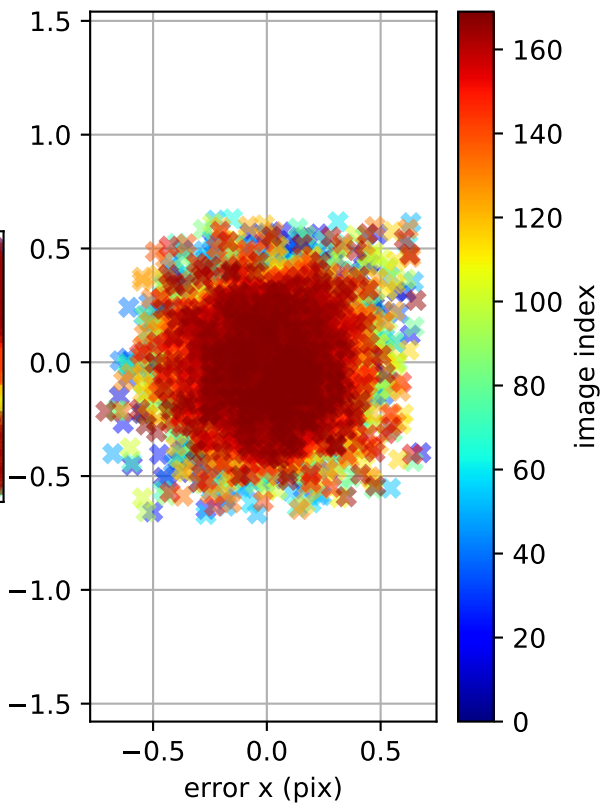
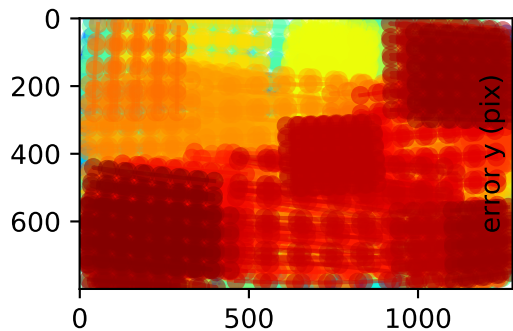
cam4: polar error



cam4: azimuthal error



# cam4: reprojection errors



# Location of removed outlier corners

