

## Calibration results

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### Camera-system parameters:

cam0 (/camera/stereo\_right/image\_raw):

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

distortion: [-0.25137138 0.09373969 0.00079234 -0.00104808] +- [0.00104231 0.00218263 0.00007159 0.00007007]

projection: [1763.63668171 1767.14040347 949.1755313 618.23371601] +- [0.16998709 0.16338859 0.51676822 0.27930391]

reprojection error: [0.000559, 0.000339] +- [0.375211, 0.347823]

cam1 (/camera/stereo\_left/image\_raw):

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

distortion: [-0.25127048 0.09336901 0.00012727 -0.0000286 ] +- [0.0009449 0.00194114 0.0000722 0.00006885]

projection: [1765.64558386 1767.93933281 942.81283269 594.34967504] +- [0.16690343 0.16179494 0.52184524 0.30371005]

reprojection error: [0.000499, 0.000339] +- [0.349151, 0.358016]

baseline T\_1\_0:

q: [ 0.00220335 -0.0029453 -0.00132387 0.99999236] +- [0.00033834 0.00059462 0.00003366]

t: [ 0.21494695 -0.00035199 -0.00341468] +- [0.0000584 0.00005244 0.00019438]

## Target configuration

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Type: aprilgrid

Tags:

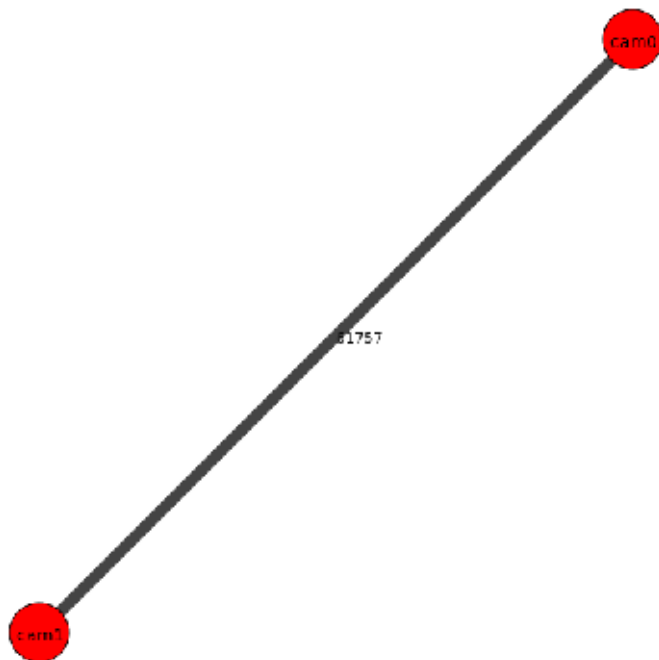
Rows: 6

Cols: 6

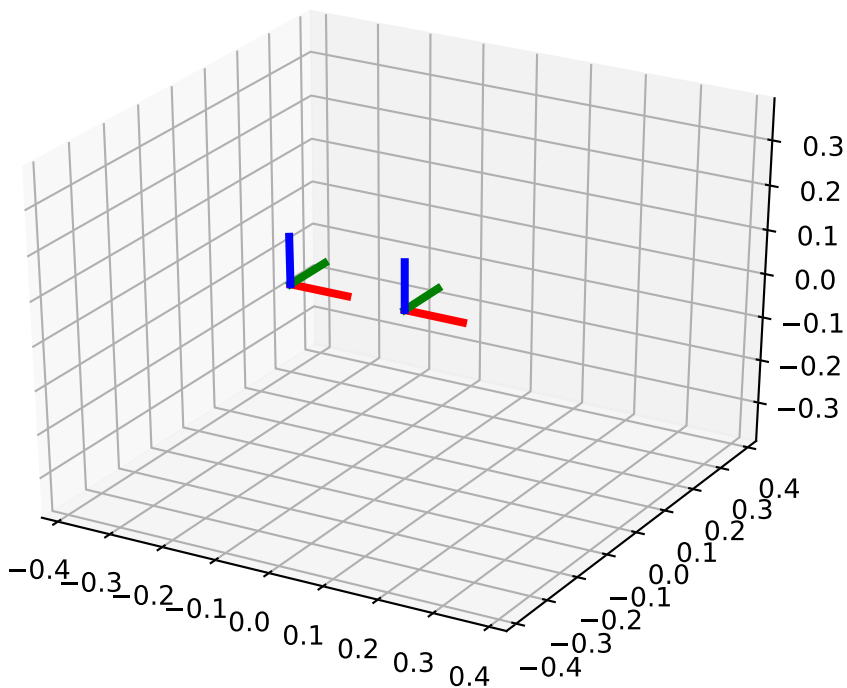
Size: 0.088 [m]

Spacing 0.026399999999999996 [m]

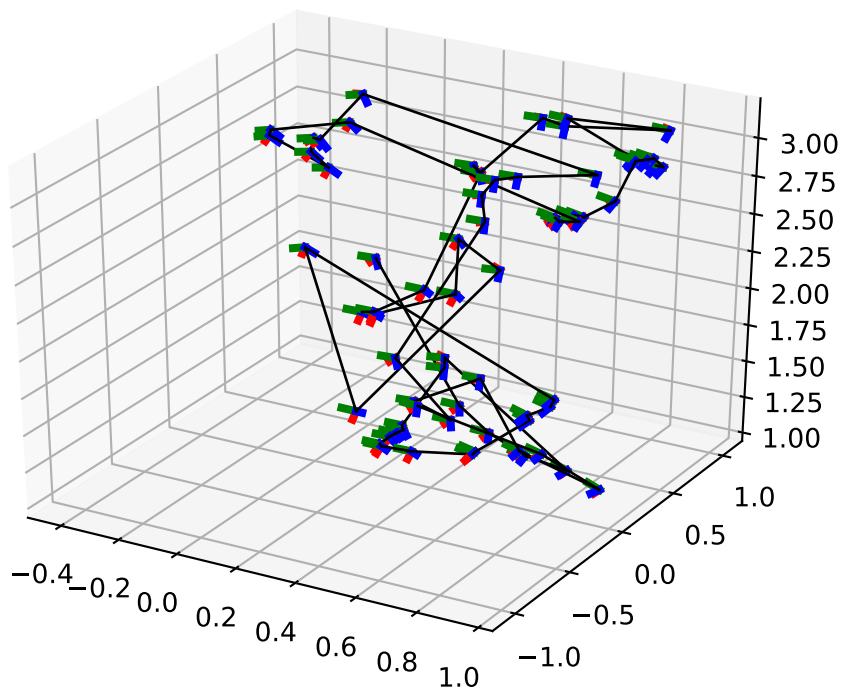
Inter-camera observations graph (edge weight=#mutual obs.)



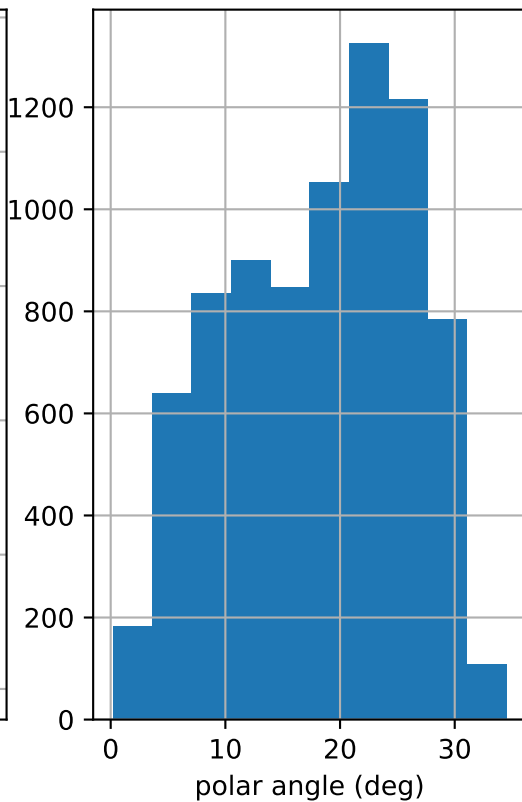
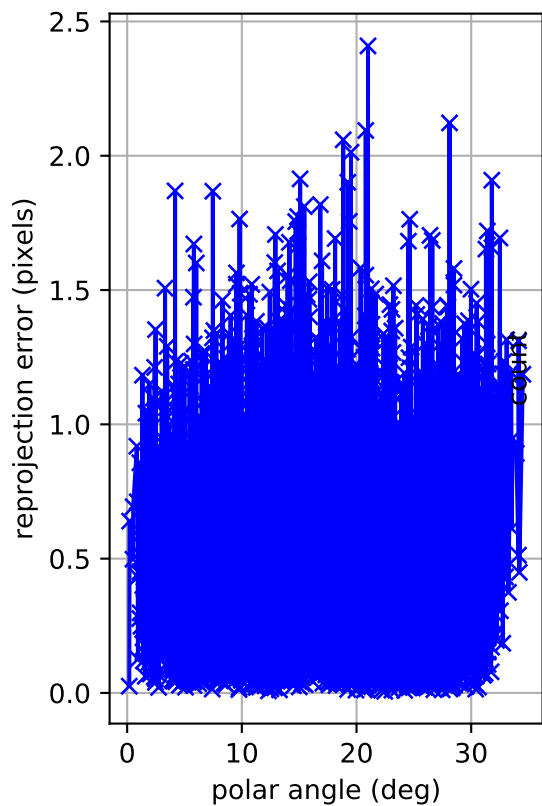
camera system



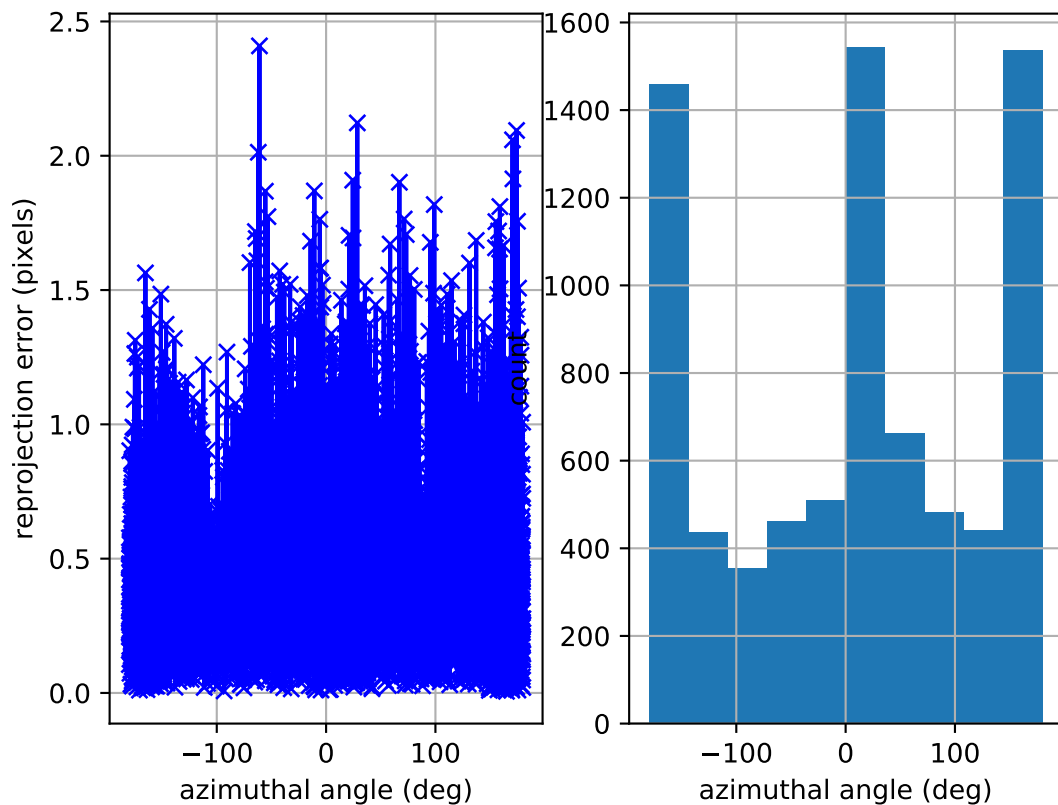
cam0: estimated poses



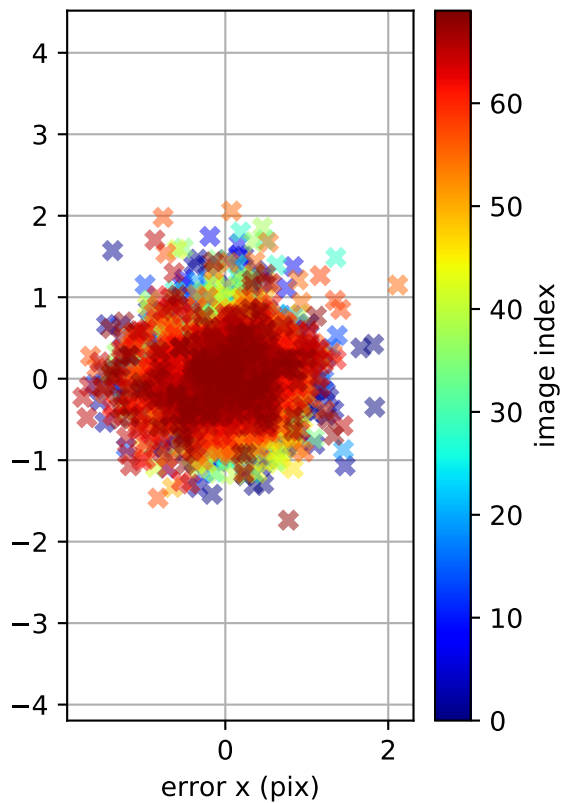
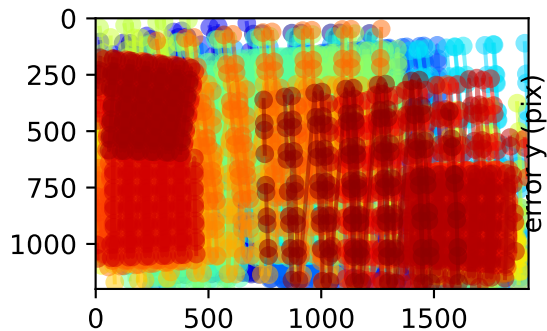
cam0: polar error



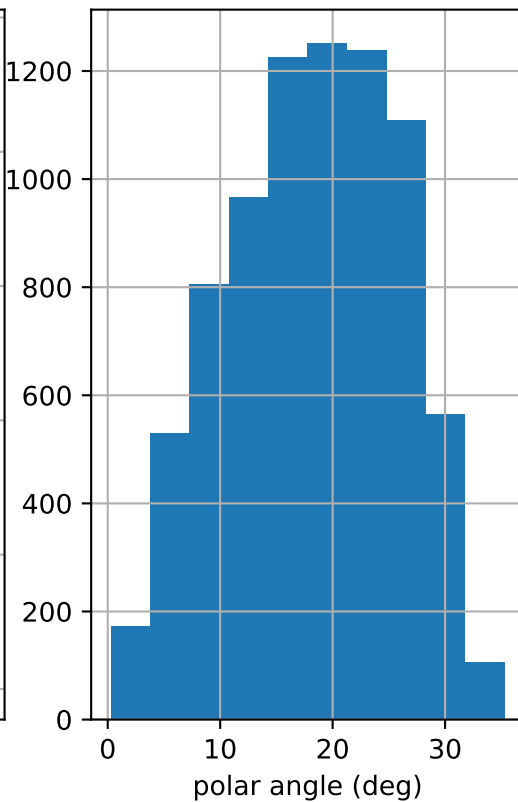
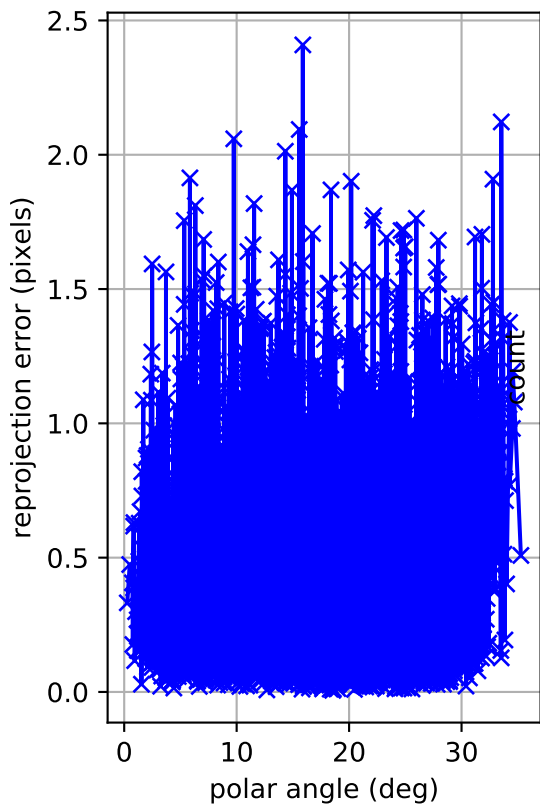
cam0: azimuthal error



cam0: reprojection errors

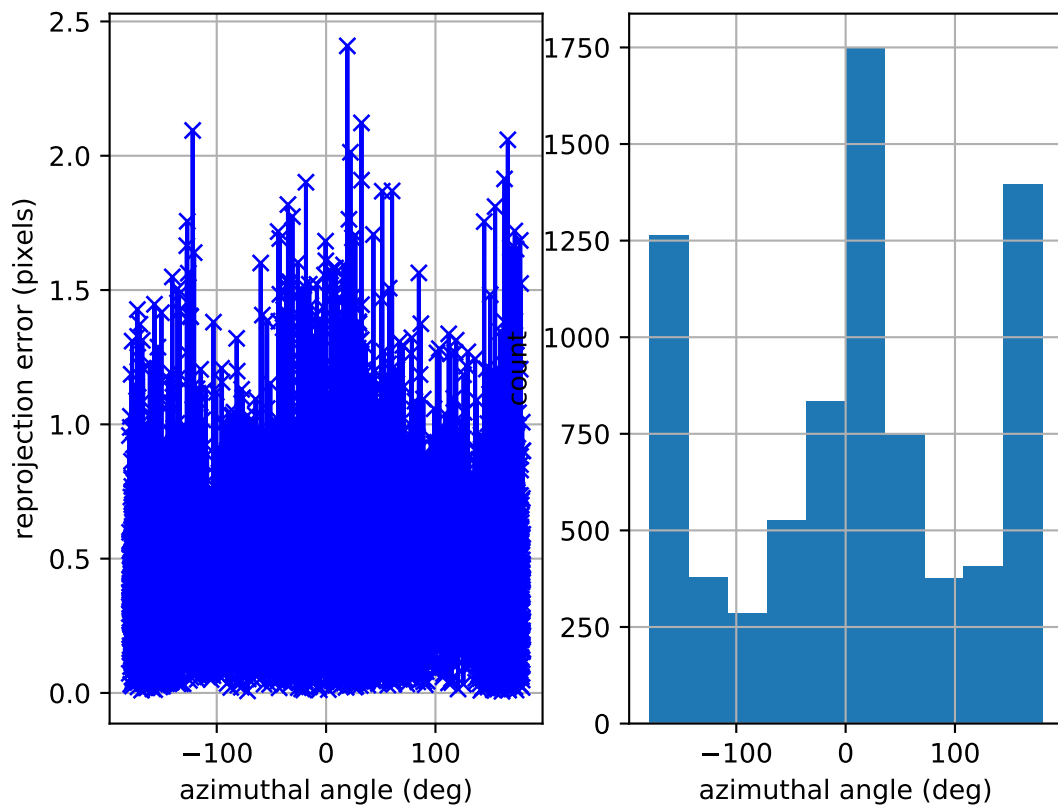


cam1: polar error

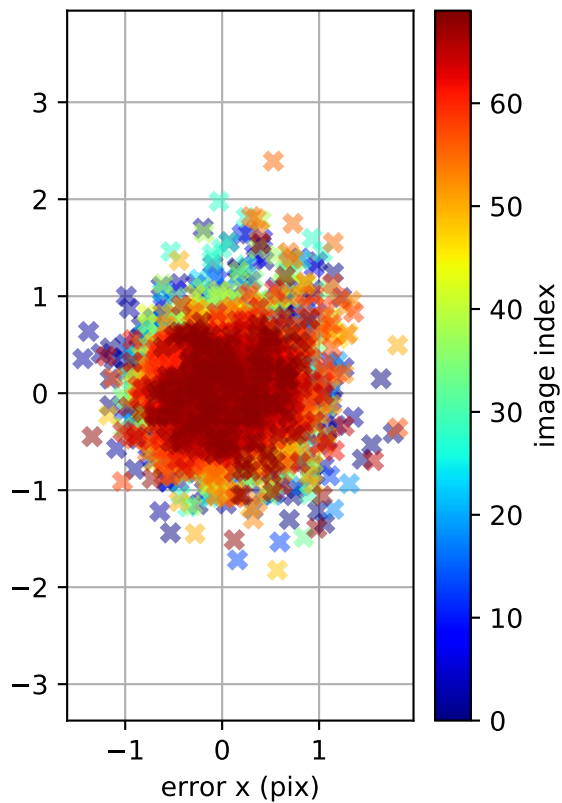
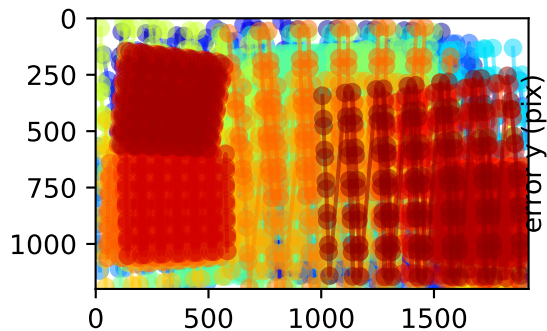




cam1: azimuthal error



cam1: reprojection errors



# Location of removed outlier corners

