

## Calibration results

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### Camera-system parameters:

cam0 (/stereo\_inertial\_publisher/left/image\_rect):

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

distortion: [-0.00708832 -0.03373663 -0.00358466 0.00053398] +- [0.00368944 0.00411491 0.00055594 0.00078571]

projection: [405.05676513 405.24850633 309.16421246 202.07247963] +- [1.31420631 1.30569243 1.24061867 1.1244313]

reprojection error: [0.000010, 0.000000] +- [0.234894, 0.179665]

cam1 (/stereo\_inertial\_publisher/right/image\_rect):

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

distortion: [0.01012495 -0.05534845 -0.00145826 0.00079267] +- [0.00359939 0.00458154 0.00056634 0.00069697]

projection: [404.4388806 404.69140989 309.32163877 201.27035965] +- [1.25635856 1.26509201 1.19632499 1.04340571]

reprojection error: [-0.000009, -0.000000] +- [0.244227, 0.184292]

### baseline T\_1\_0:

q: [0.0007338 -0.00009781 0.00001758 0.99999973] +- [0.00133175 0.0023679 0.00024172]

t: [-0.0749683 0.00040576 -0.00061056] +- [0.00009814 0.00006423 0.00025612]

## Target configuration

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Type: aprilgrid

Tags:

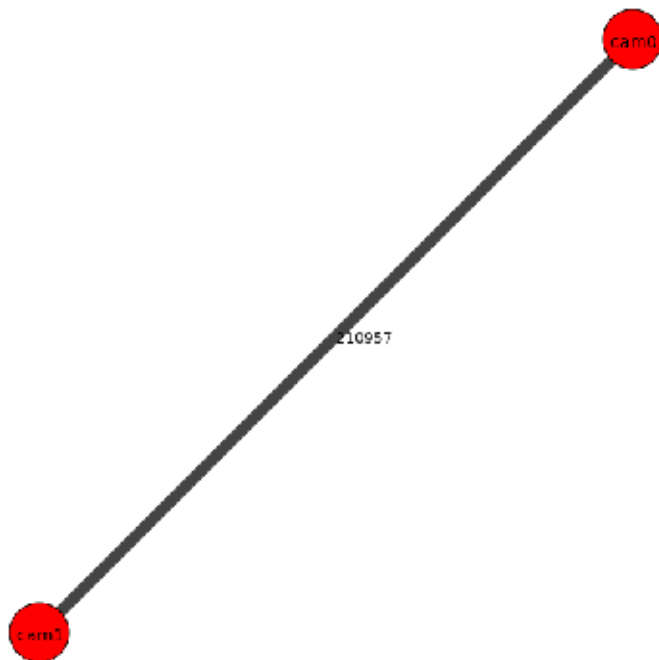
Rows: 3

Cols: 3

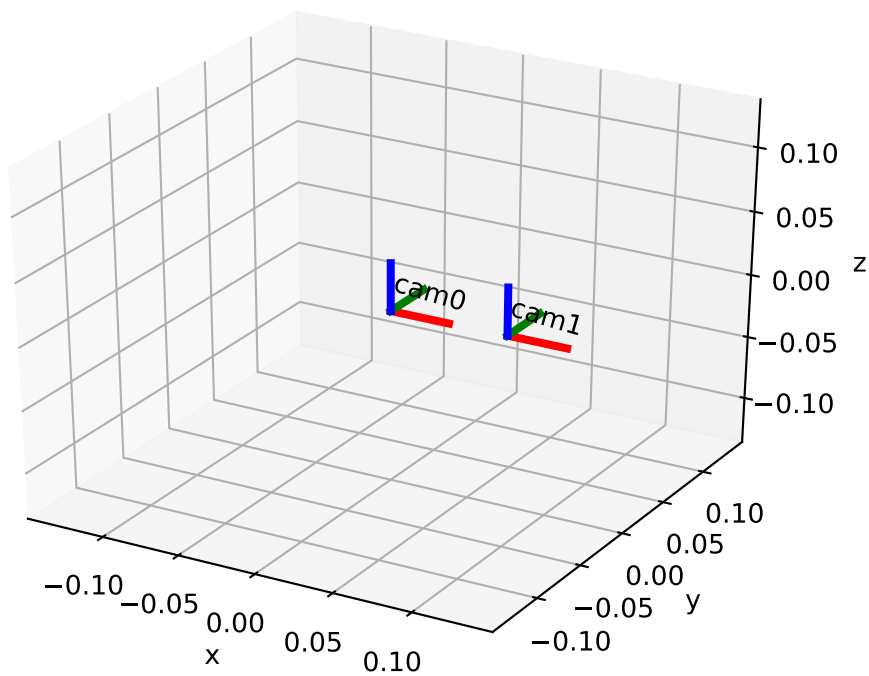
Size: 0.05 [m]

Spacing 0.010000000000000002 [m]

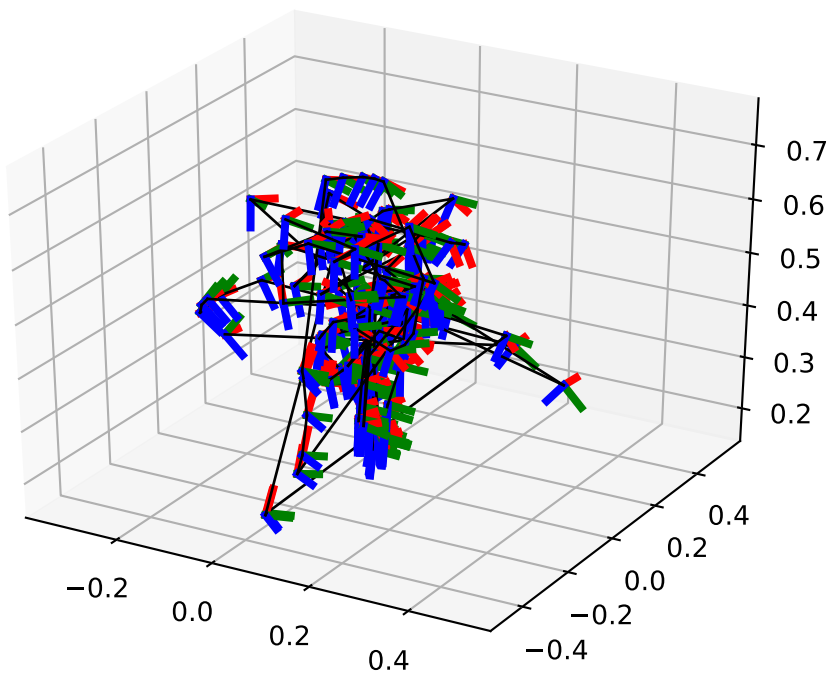
Inter-camera observations graph (edge weight=#mutual obs.)



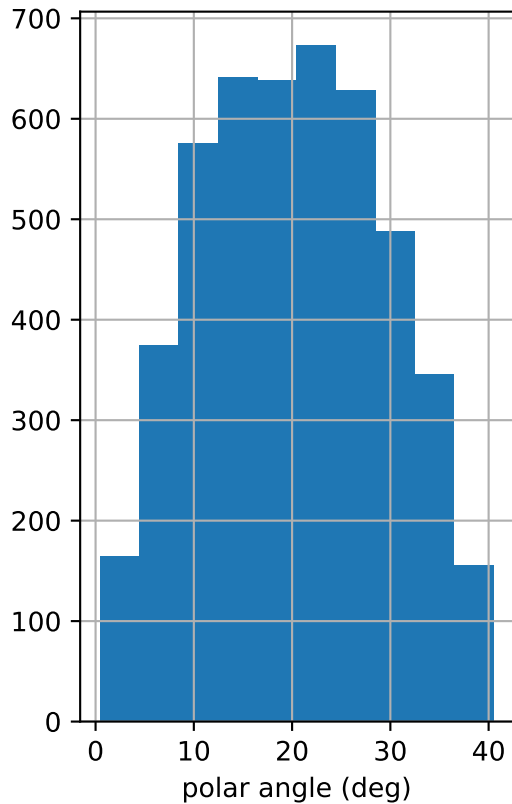
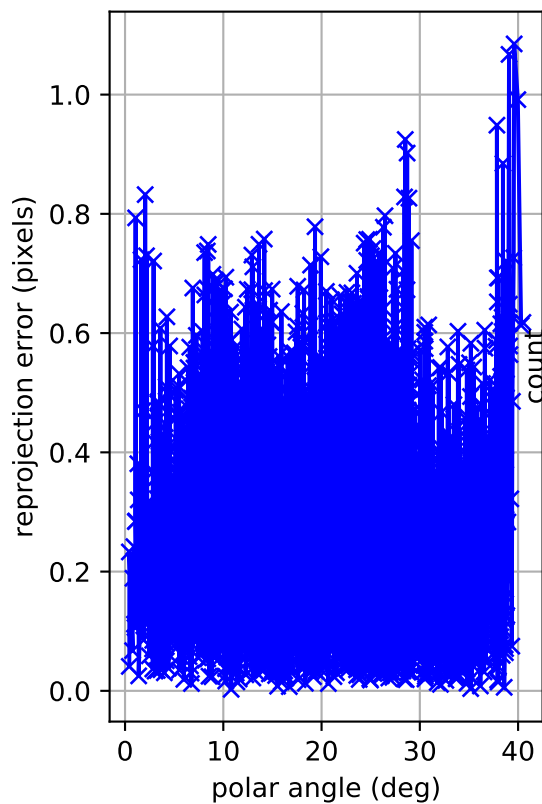
camera system



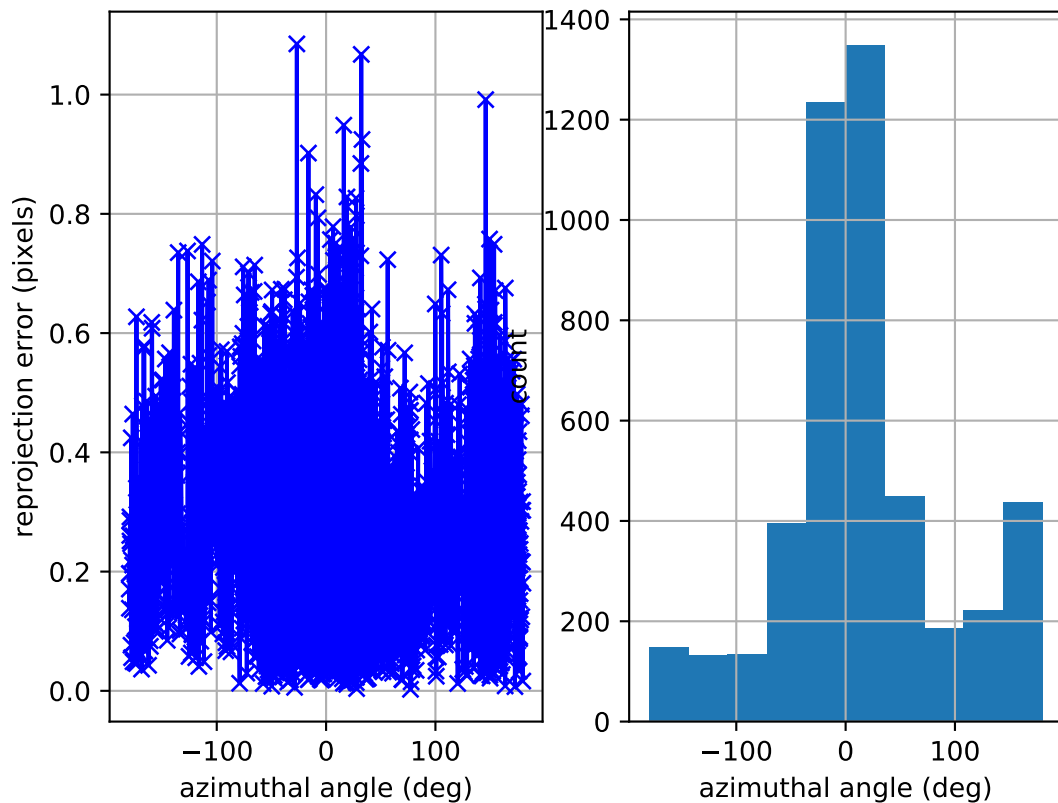
cam0: estimated poses



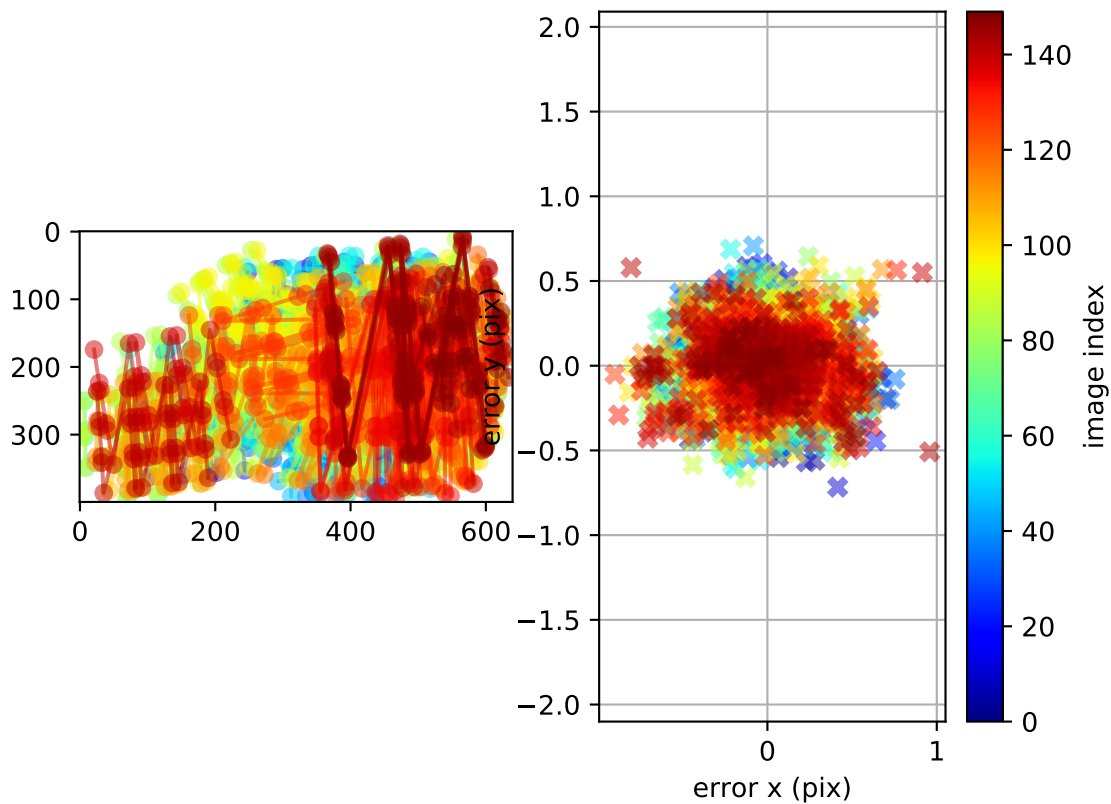
cam0: polar error



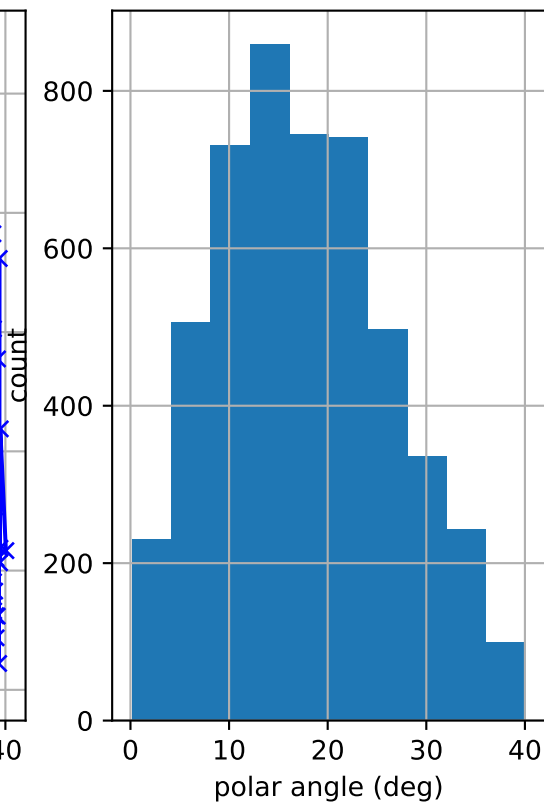
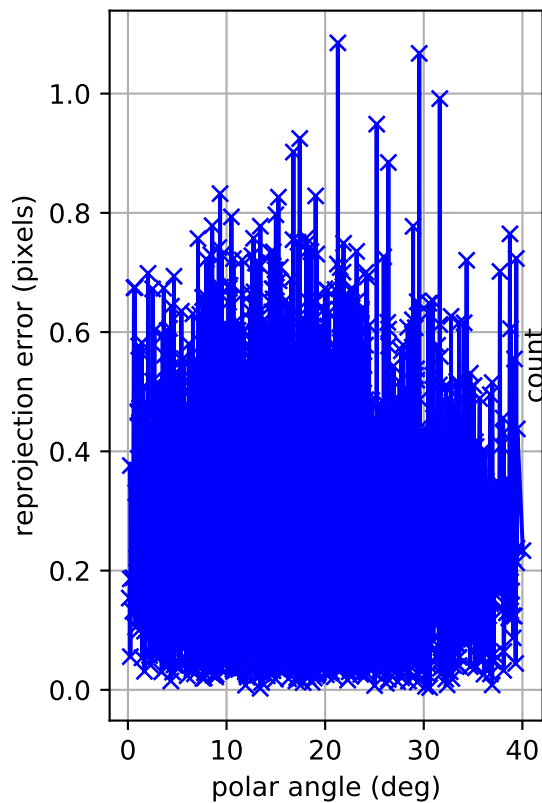
cam0: azimuthal error



cam0: reprojection errors

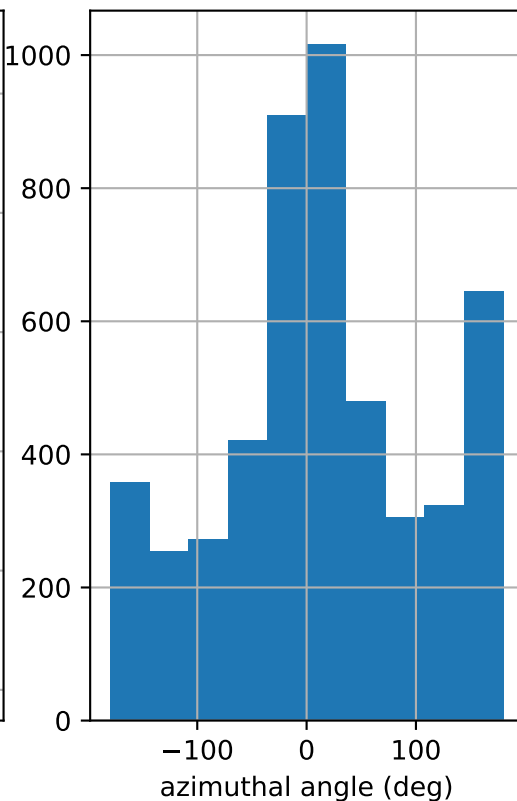
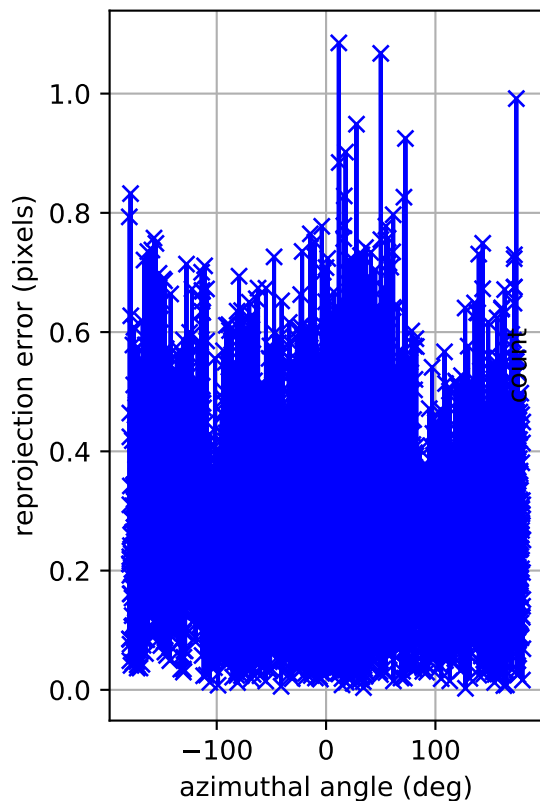


cam1: polar error

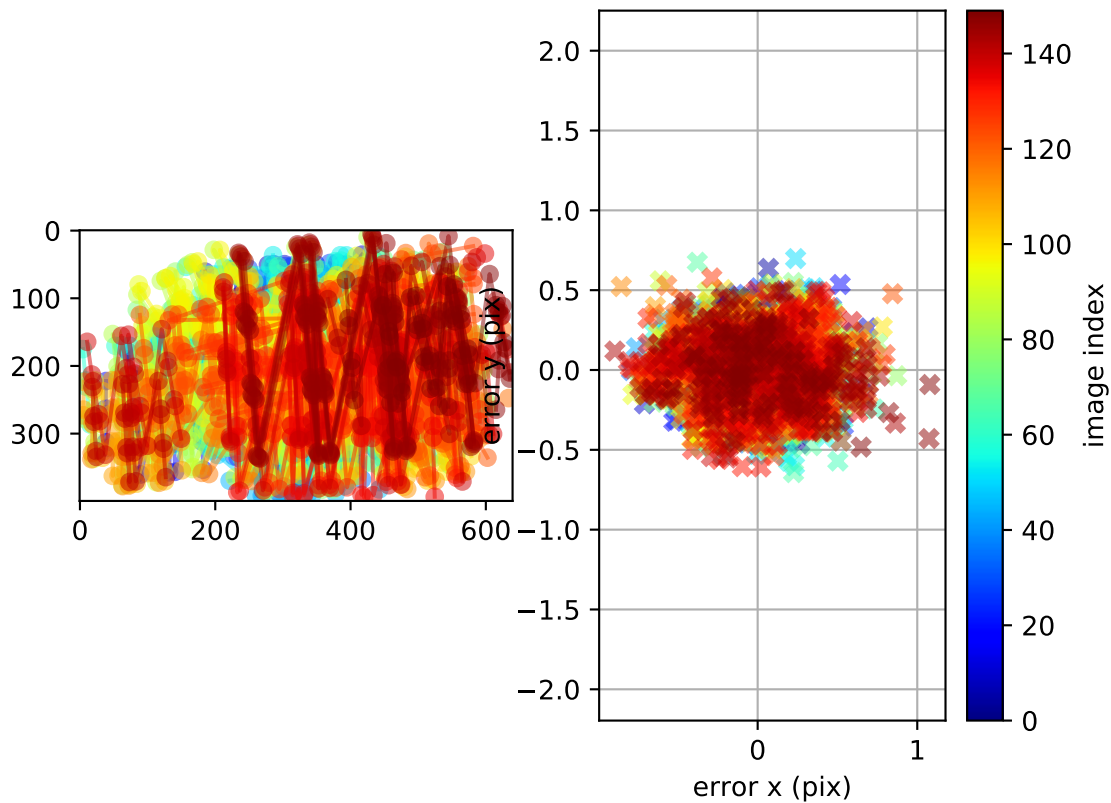




cam1: azimuthal error



cam1: reprojection errors



# Location of removed outlier corners

