

## Calibration results

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### Camera-system parameters:

cam0 (/front\_camera/left/image\_raw):

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

distortion: [ 0.02479735 -0.06685379 0.07272744 -0.02420449] +- [0.00246172 0.00619238 0.00609592 0.00206414]

projection: [568.75849371 568.0898834 633.81448428 346.3098741 ] +- [0.13152436 0.12907026 0.11731401 0.29772191]

reprojection error: [-0.000062, -0.000003] +- [0.255298, 0.238166]

cam1 (/front\_camera/right/image\_raw):

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

distortion: [-0.00484293 0.01259368 -0.00713851 0.00274209] +- [0.00221007 0.00534579 0.00505821 0.00164659]

projection: [570.08541612 569.26919713 633.03480937 324.40346048] +- [0.12969253 0.12736334 0.12069519 0.30290212]

reprojection error: [0.000014, -0.000002] +- [0.260675, 0.248088]

cam2 (/front\_camera/rgb/image\_raw):

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

distortion: [ 0.17823893 -0.53802177 1.12431793 -0.75221461] +- [0.00584902 0.03043821 0.06192394 0.04269393]

projection: [1163.10892036 1162.75746084 963.43542628 531.2941023 ] +- [0.12092094 0.12091259 0.00285598 0.02610455]

reprojection error: [0.000349, 0.000351] +- [0.491924, 0.578744]

### baseline T\_1\_0:

q: [ 0.00193088 0.00534945 -0.00271015 0.99998015] +- [0.00019958 0.00040061 0.00006207]

t: [-0.07532289 -0.00023578 -0.00054913] +- [0.00004324 0.00003719 0.00006964]

### baseline T\_2\_1:

q: [ 0.00416866 -0.00284649 0.00109447 0.99998666] +- [0.00060981 0.00032294 0.00018642]

t: [0.03555478 0.00110396 0.00020111] +- [0.00012769 0.0001058 0.00019871]

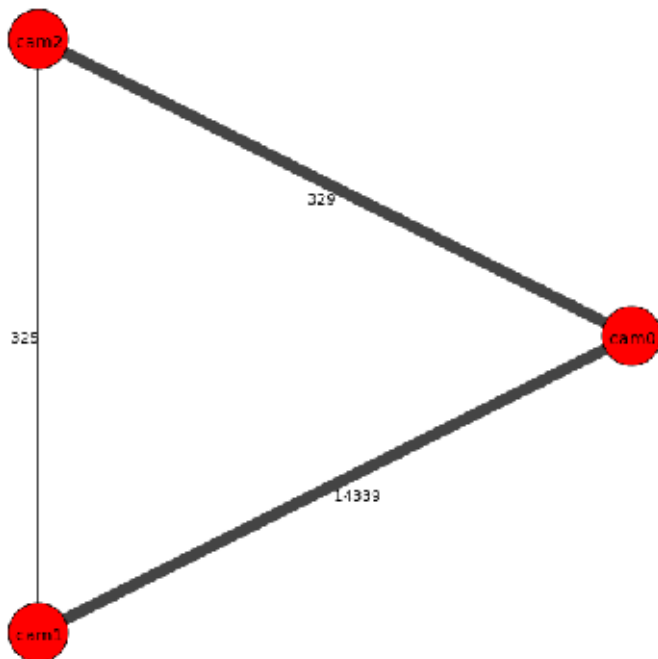
## Target configuration

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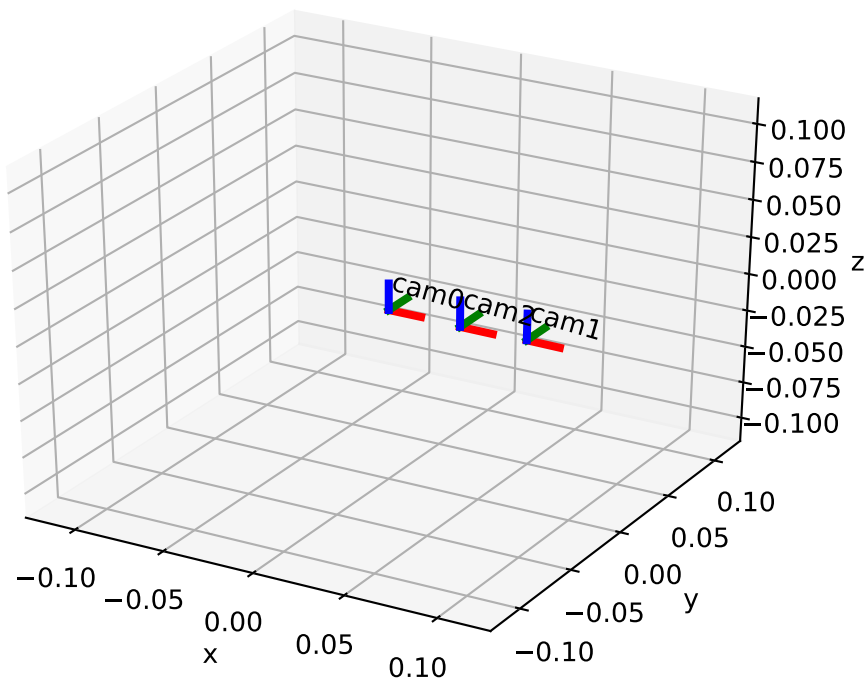
Type: aprilgrid

Tags:  
Rows: 6  
Cols: 6  
Size: 0.0294 [m]  
Spacing 0.00882 [m]

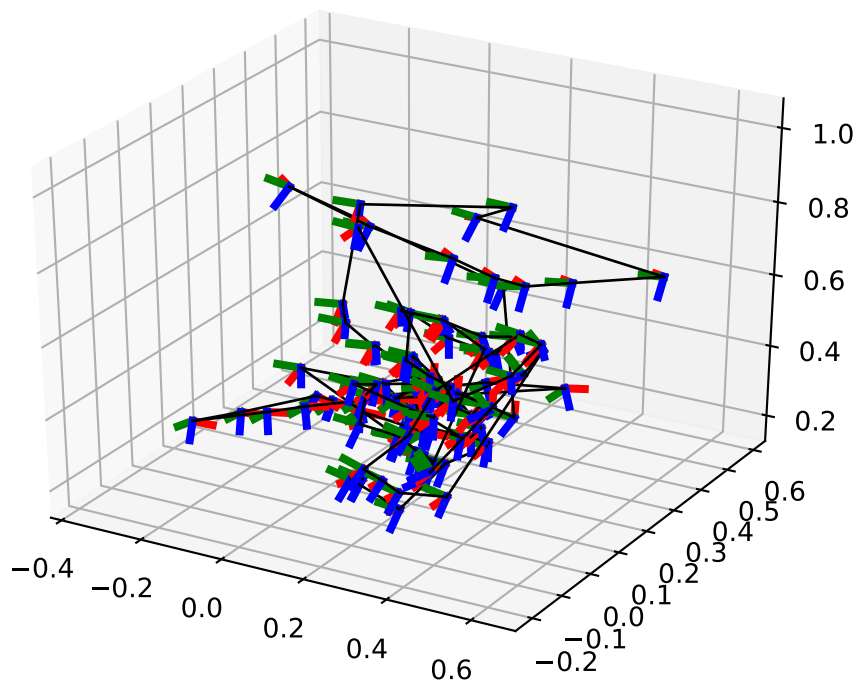
Inter-camera observations graph (edge weight=#mutual obs.)



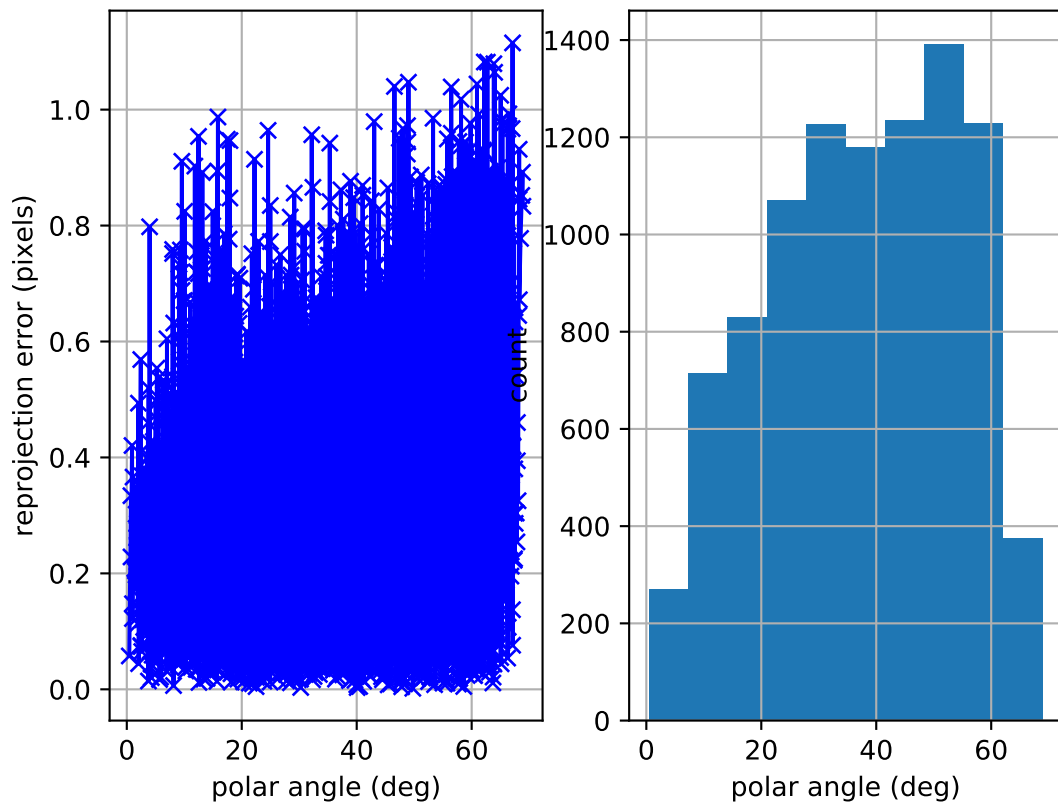
camera system



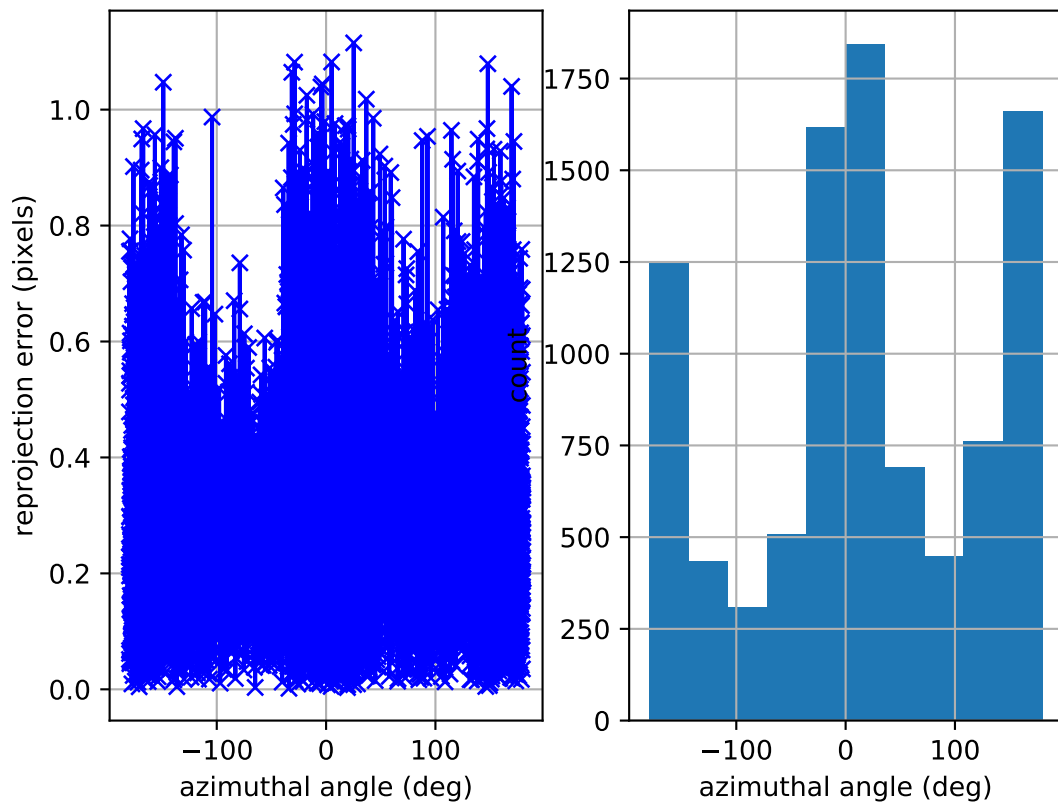
cam0: estimated poses



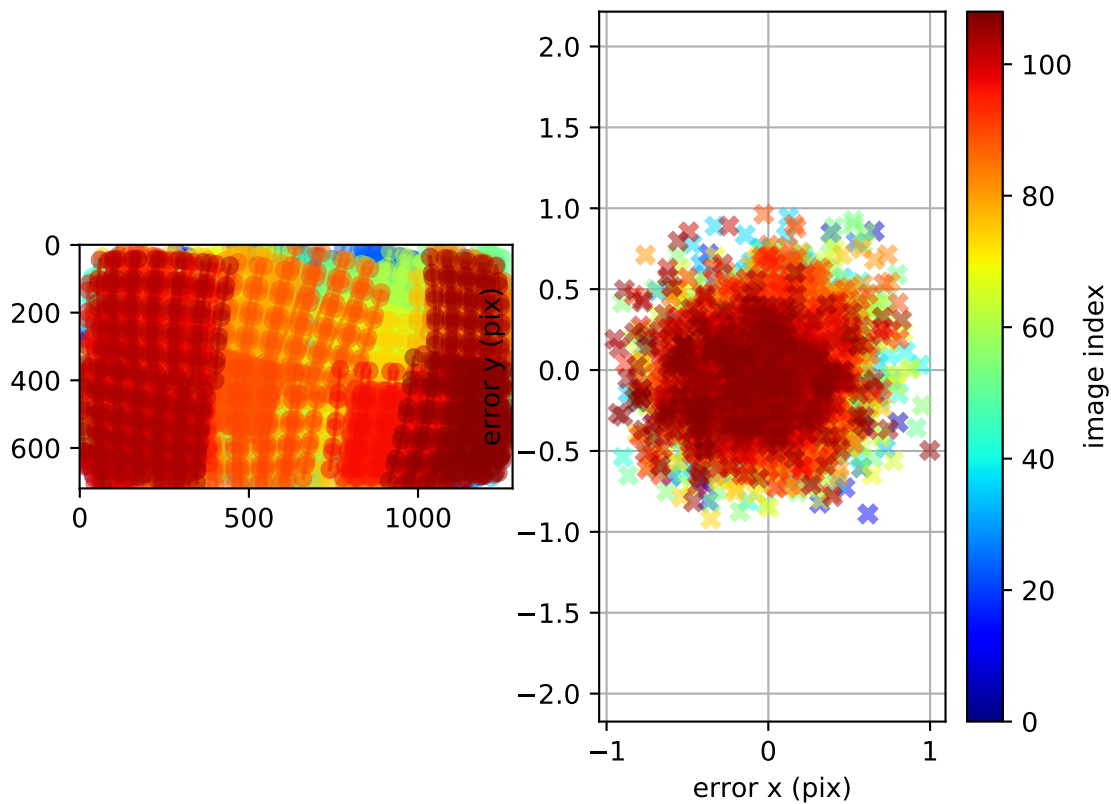
cam0: polar error



cam0: azimuthal error

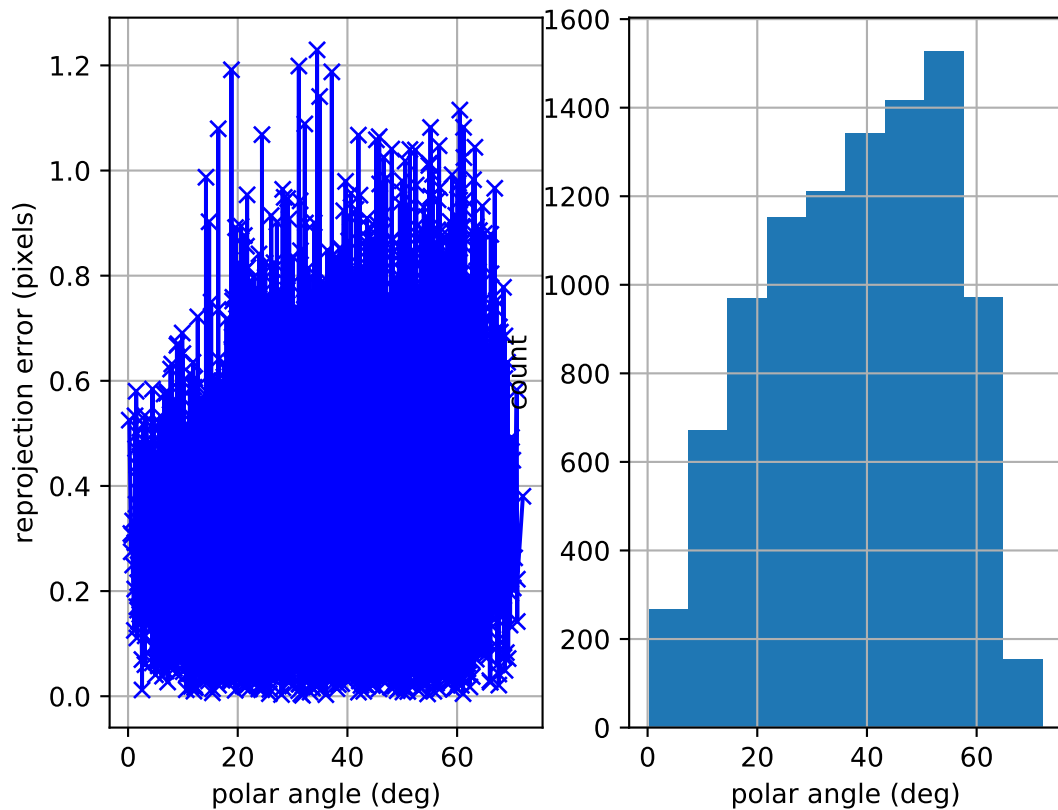


cam0: reprojection errors

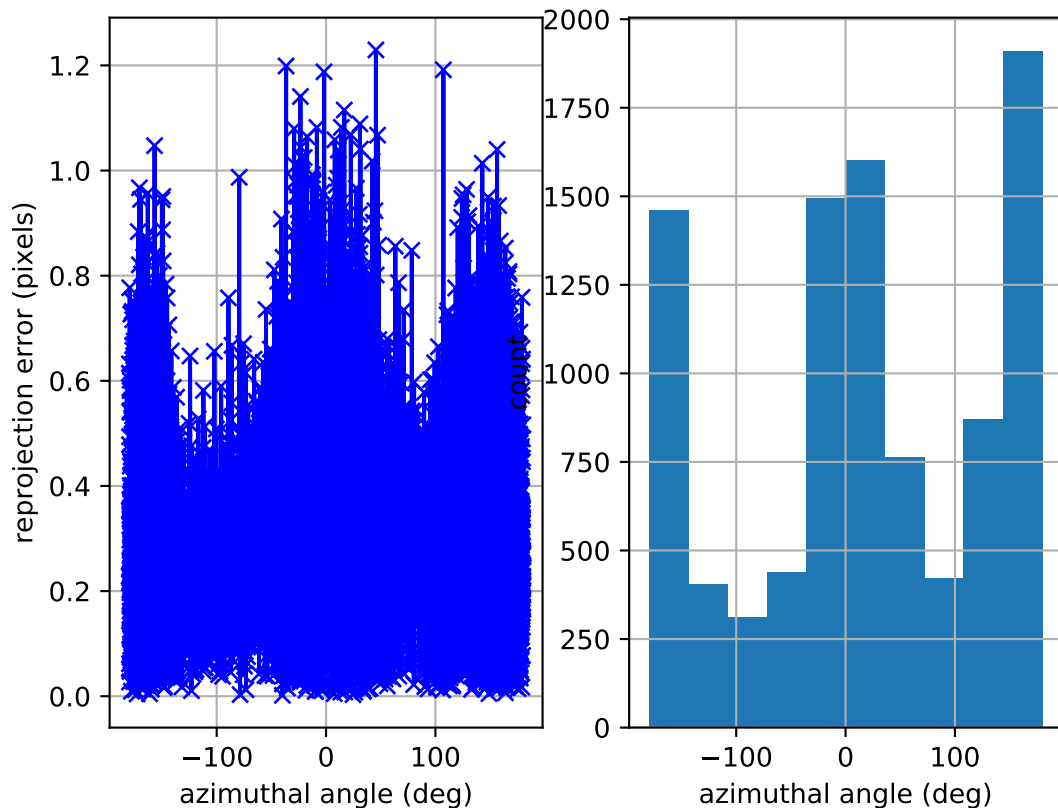




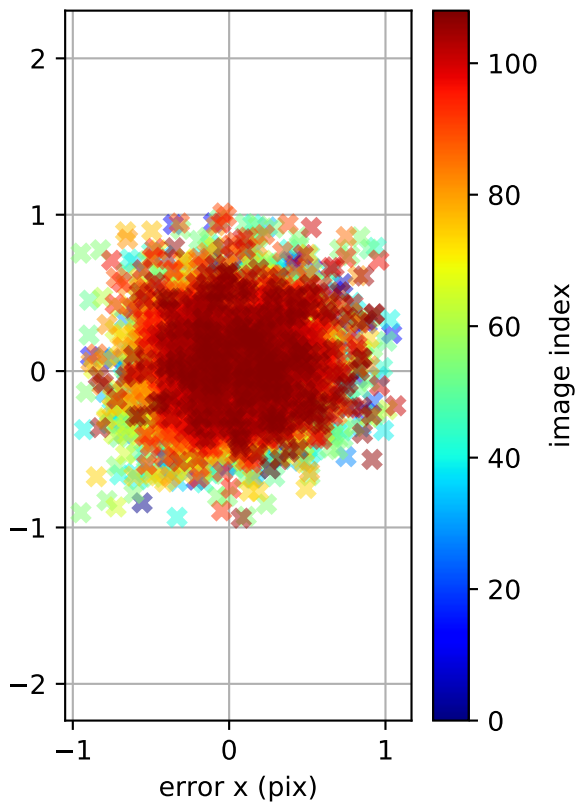
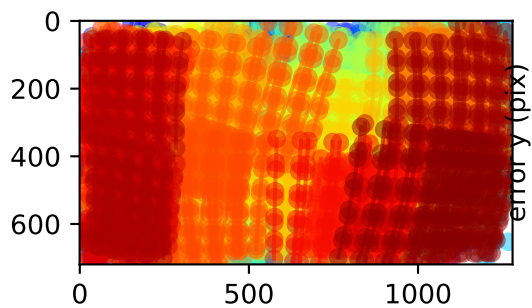
cam1: polar error



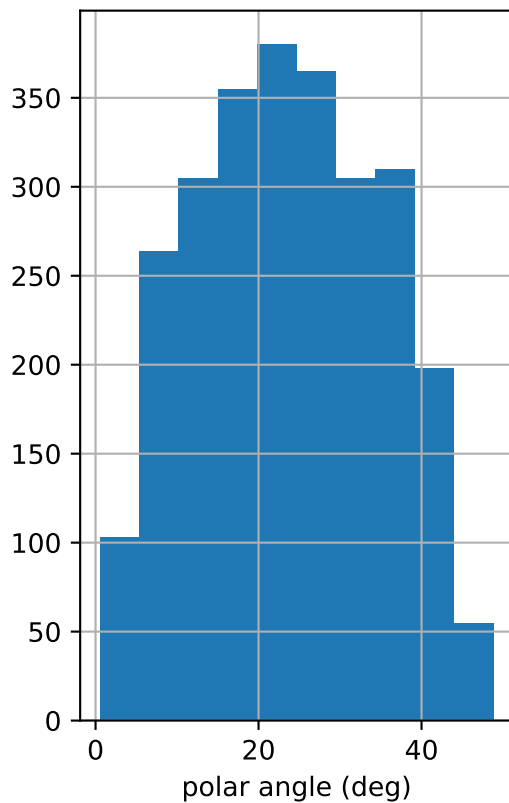
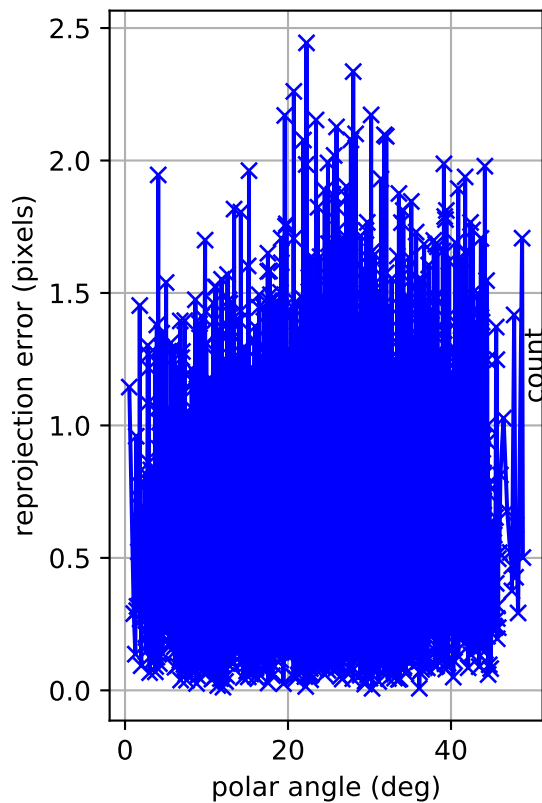
cam1: azimuthal error



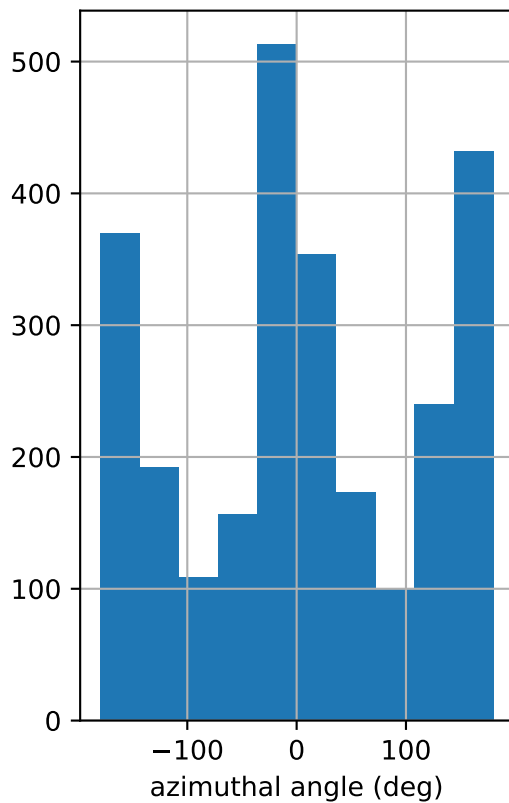
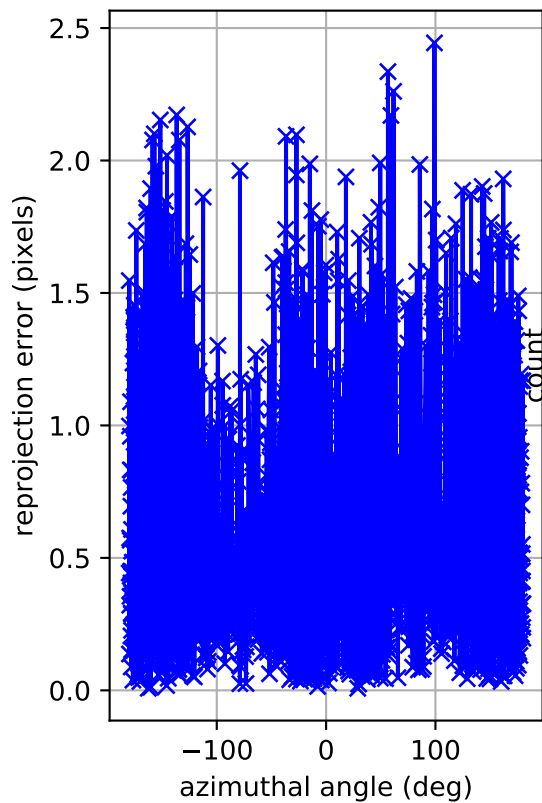
cam1: reprojection errors



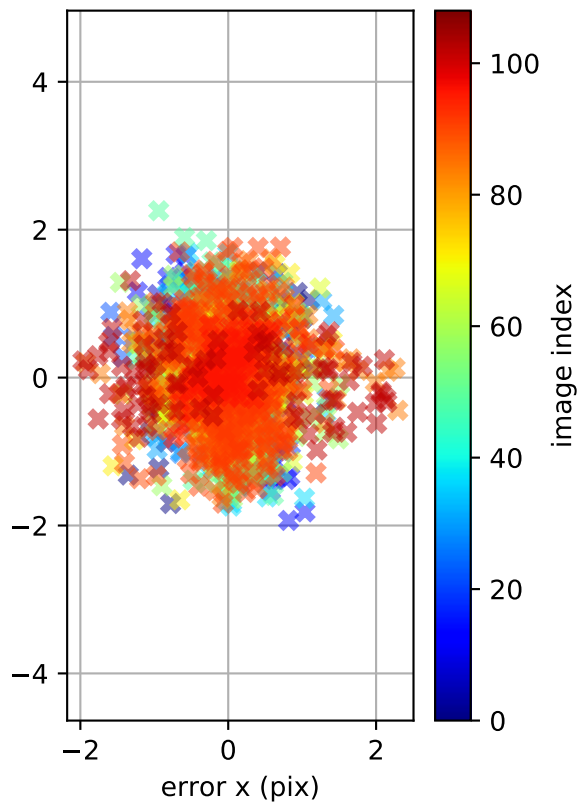
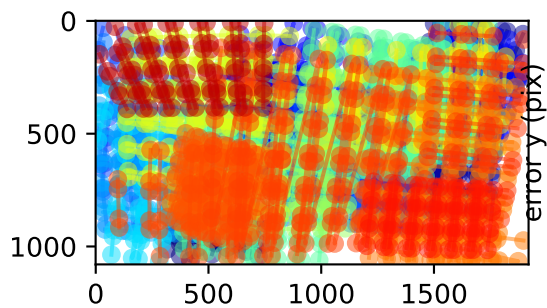
cam2: polar error



cam2: azimuthal error

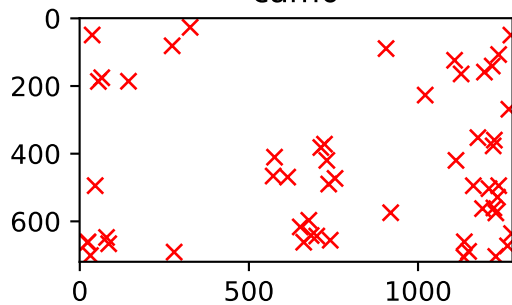


cam2: reprojection errors

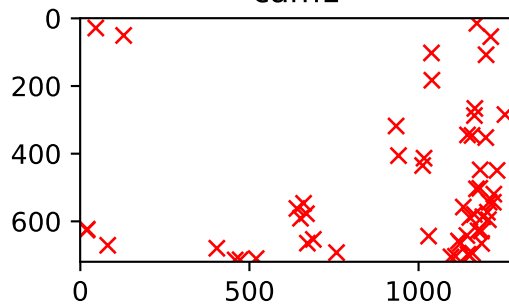


# Location of removed outlier corners

cam0



cam1



cam2

