

## Calibration results

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### Camera-system parameters:

cam0 (/infra\_left):

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

distortion: [ 0.00380073 -0.00312817 0.00010663 -0.00019401] +- [0.005619 0.01164594 0.00045815 0.00058574]

projection: [423.59895558 424.05850978 430.2210204 232.66727315] +- [0.4110411 0.40389654 0.47936457 0.3138913 ]

reprojection error: [0.000001, 0.000001] +- [0.028827, 0.032019]

cam1 (/infra\_right):

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

distortion: [ 0.00468015 -0.00596543 -0.0000593 -0.00045987] +- [0.00520321 0.01006974 0.00045096 0.00059262]

projection: [424.52003702 424.98099204 430.24013899 232.83822472] +- [0.40596055 0.40735006 0.48781178 0.29278121]

reprojection error: [-0.000003, 0.000001] +- [0.027743, 0.032732]

baseline T\_1\_0:

q: [-0.00027927 -0.00009797 0.00004377 0.99999996] +- [0.00131532 0.00221579 0.00012608]

t: [-0.04998172 0.00000658 -0.00011355] +- [0.00026012 0.00025948 0.00149962]

## Target configuration

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Type: checkerboard

Rows

Count: 8

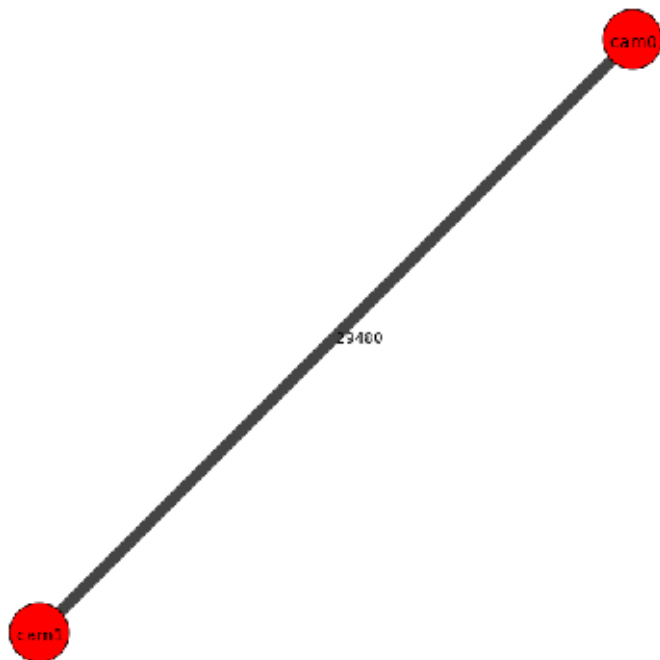
Distance: 0.03 [m]

Cols

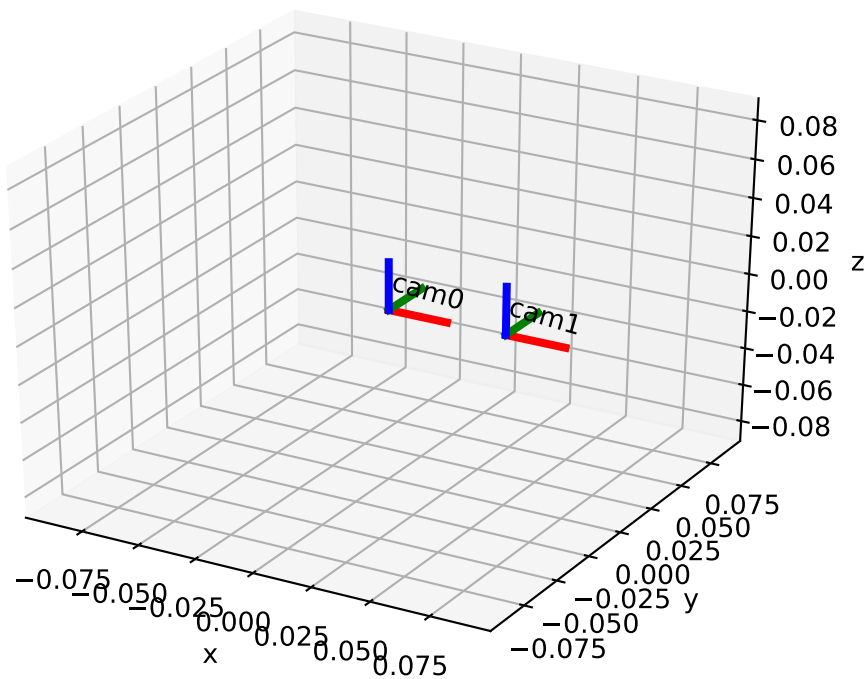
Count: 11

Distance: 0.03 [m]

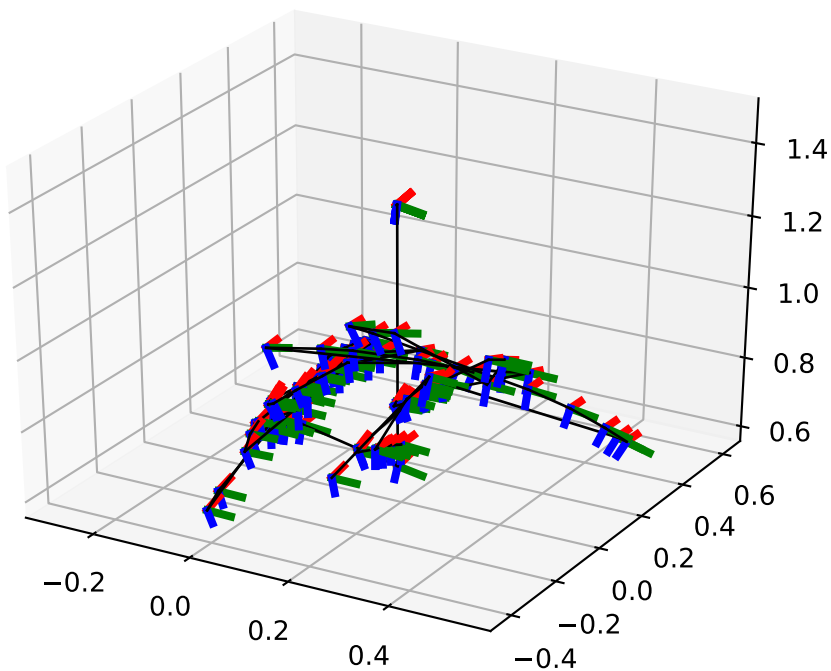
Inter-camera observations graph (edge weight=#mutual obs.)



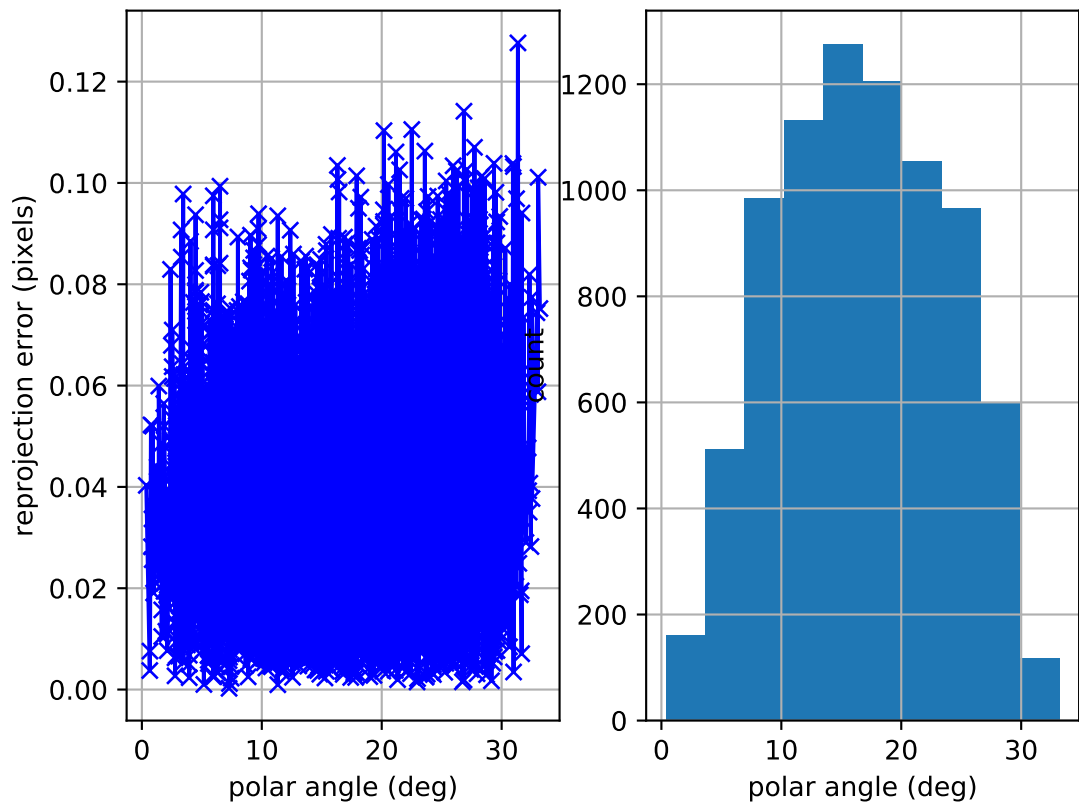
camera system



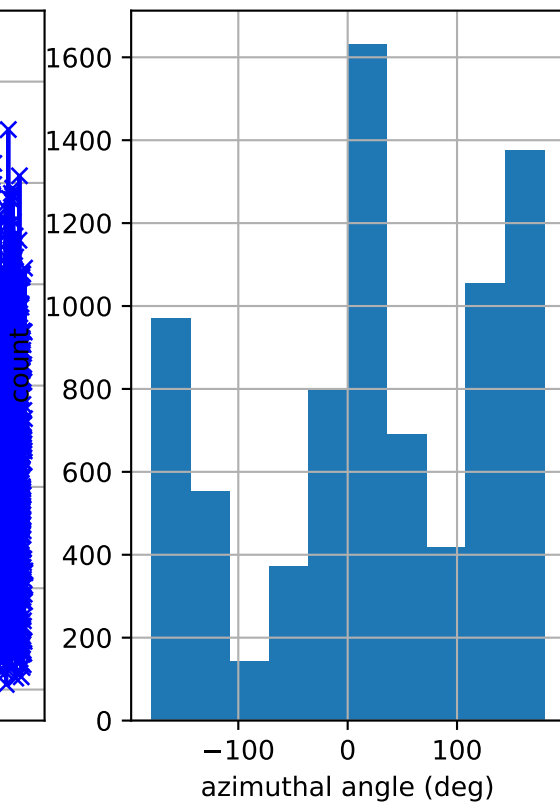
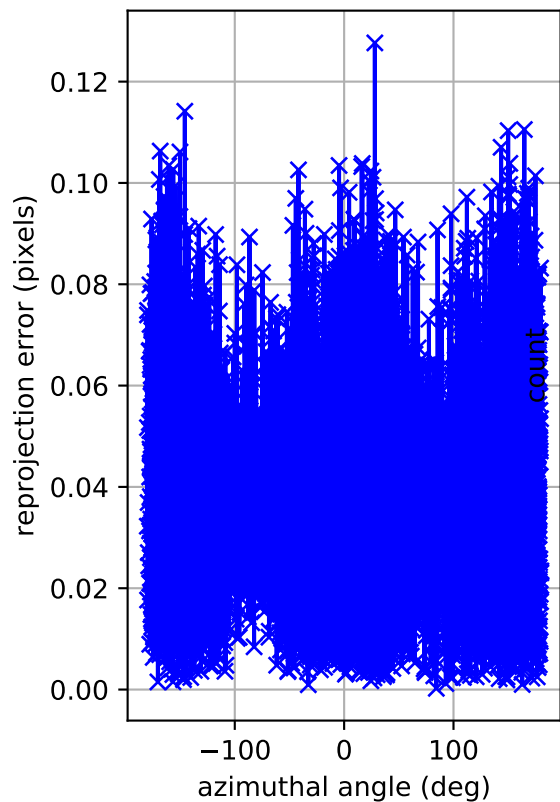
cam0: estimated poses



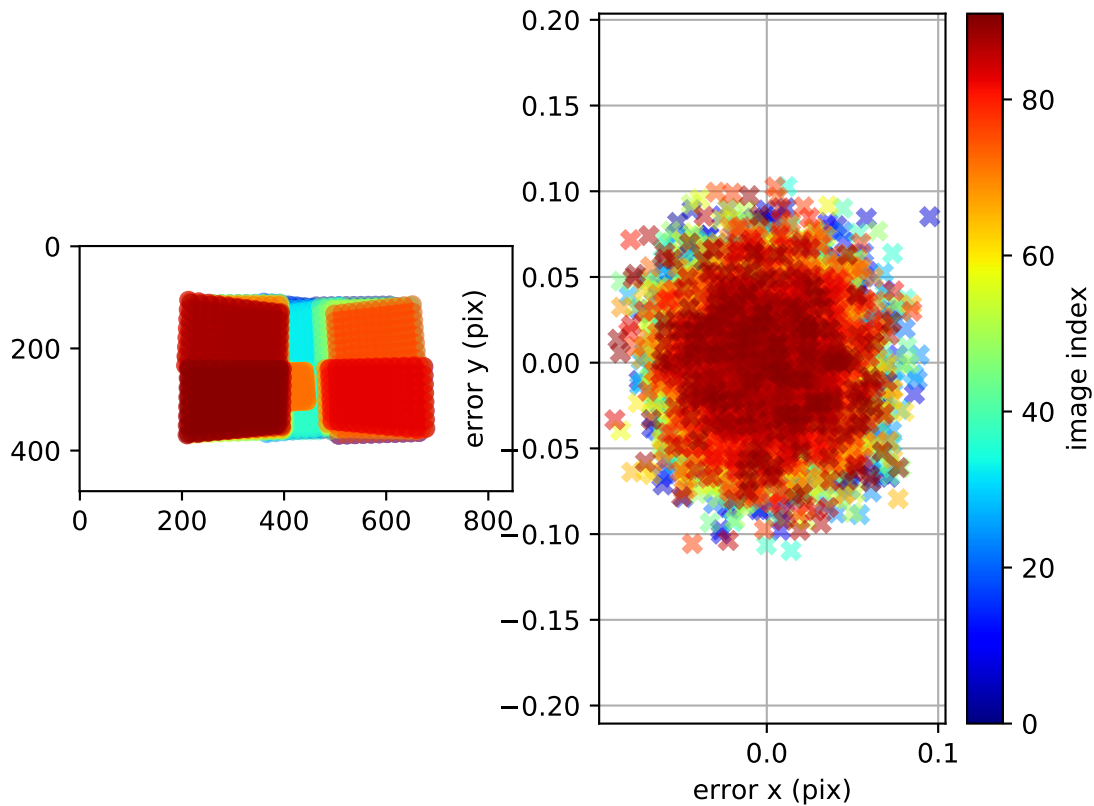
cam0: polar error



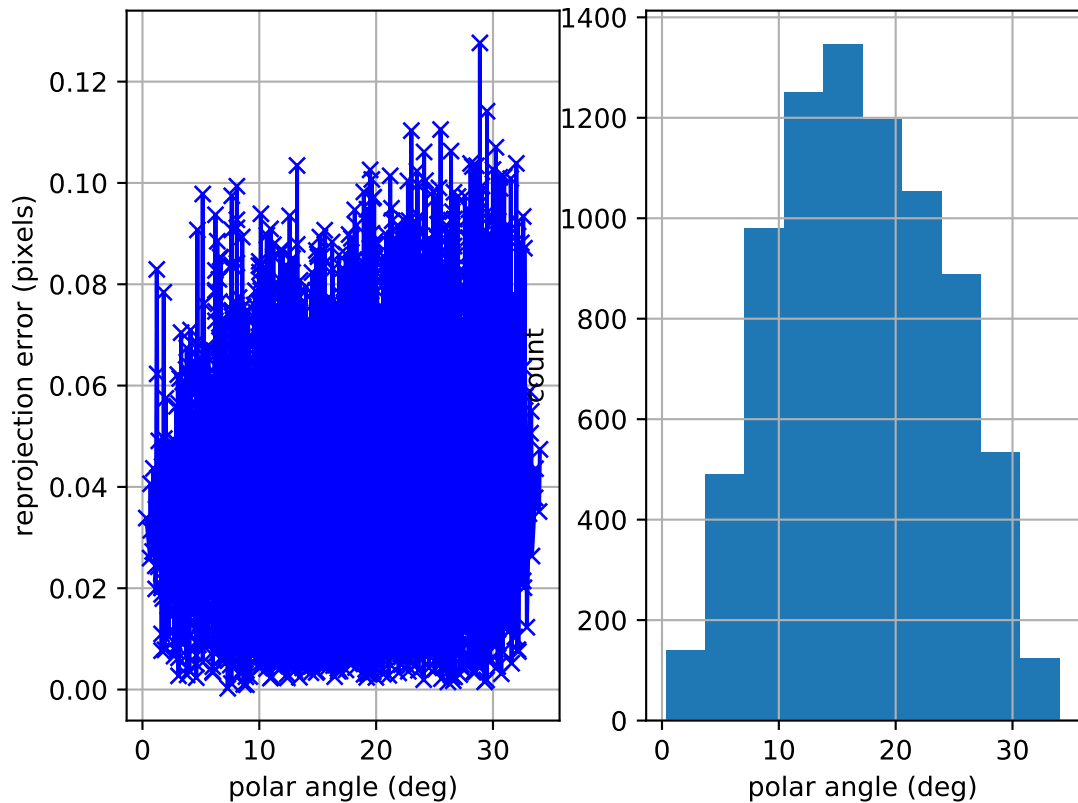
cam0: azimuthal error



cam0: reprojection errors

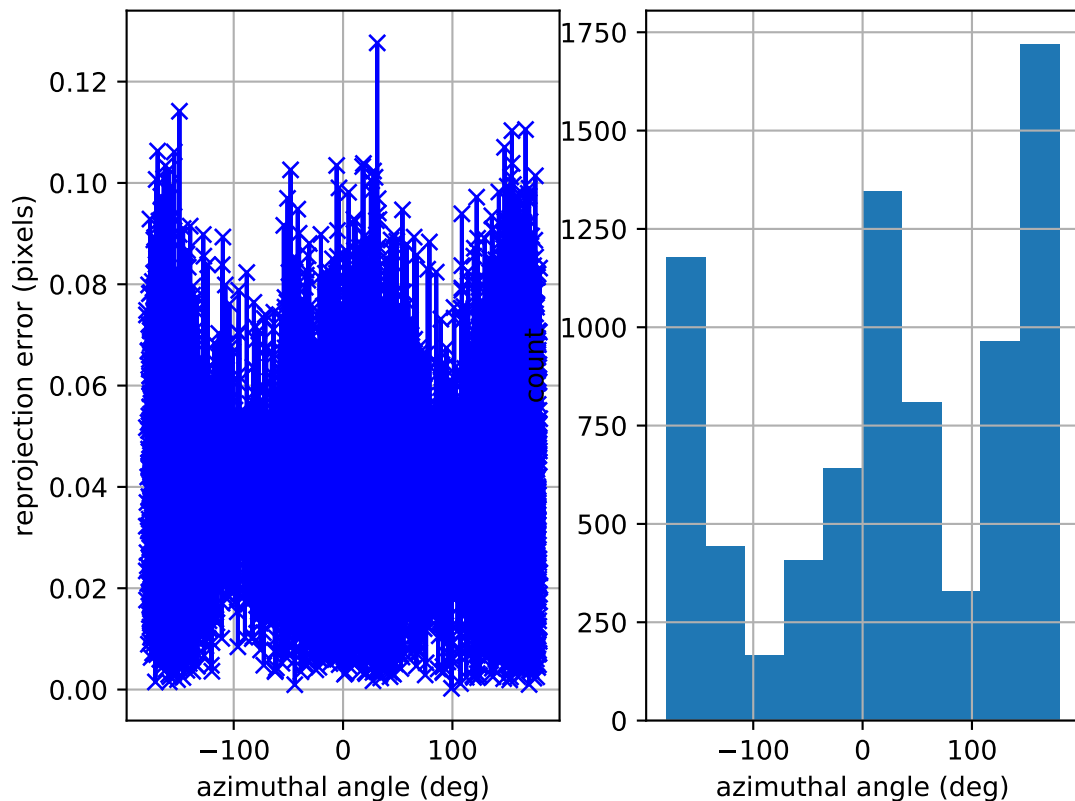


cam1: polar error





cam1: azimuthal error



cam1: reprojection errors

