

## Calibration results

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### Camera-system parameters:

cam0 (/zed\_node/left/image\_rect\_color):

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

distortion: [ 0.43118318 0.26332419 -0.0084063 0.00851498] +- [ 0.00617792 0.01953534 0.00144442 0.00121263]

projection: [ 502.13326403 501.30297323 326.8751236 171.21555893] +- [ 0.26885594 0.29362892 0.60503406 0.83094579]

reprojection error: [-0.000015, 0.000029] +- [0.184460, 0.147973]

cam1 (/zed\_node/right/image\_rect\_color):

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

distortion: [ 0.4311818 0.26332239 -0.00840544 0.00851538] +- [ 0.00617782 0.01953513 0.00144443 0.00121261]

projection: [ 502.13336864 501.3029352 326.87551825 171.21611784] +- [ 0.26885813 0.2936314 0.60504378 0.83095423]

reprojection error: [-0.000048, 0.000028] +- [0.184462, 0.147971]

### baseline T\_1\_0:

q: [-0.00000055 0.0000004 -0.00000008 1. ] +- [ 0.00151104 0.00232157 0.00014691]

t: [ 0.00000038 -0.00000006 -0.0000001 ] +- [ 0.00043811 0.00045714 0.00171803]

## Target configuration

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Type: checkerboard

Rows

Count: 8

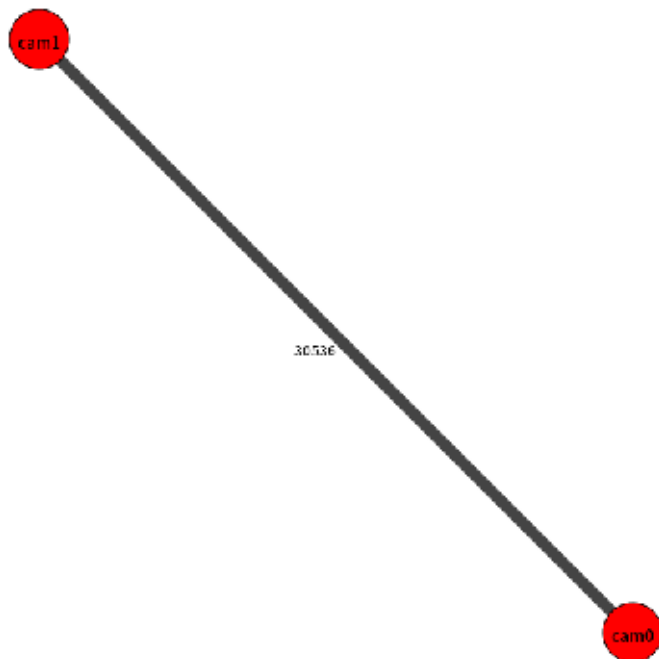
Distance: 0.15 [m]

Cols

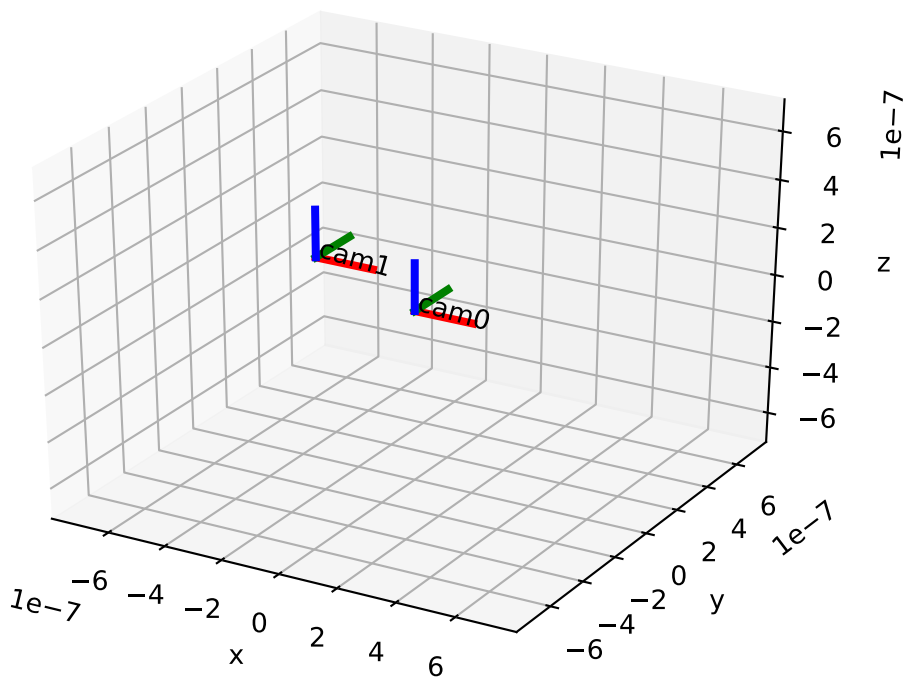
Count: 11

Distance: 0.15 [m]

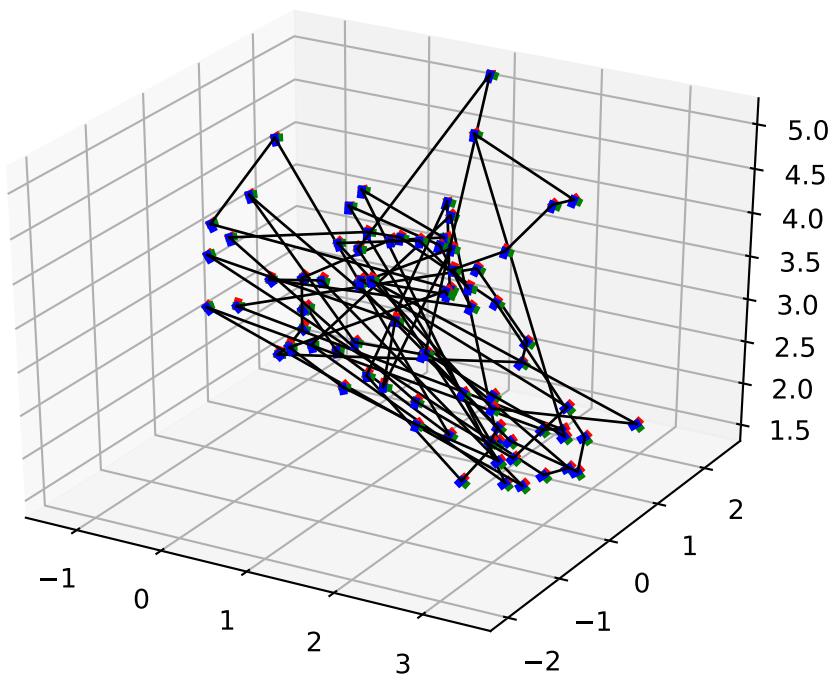
Inter-camera observations graph (edge weight=#mutual obs.)



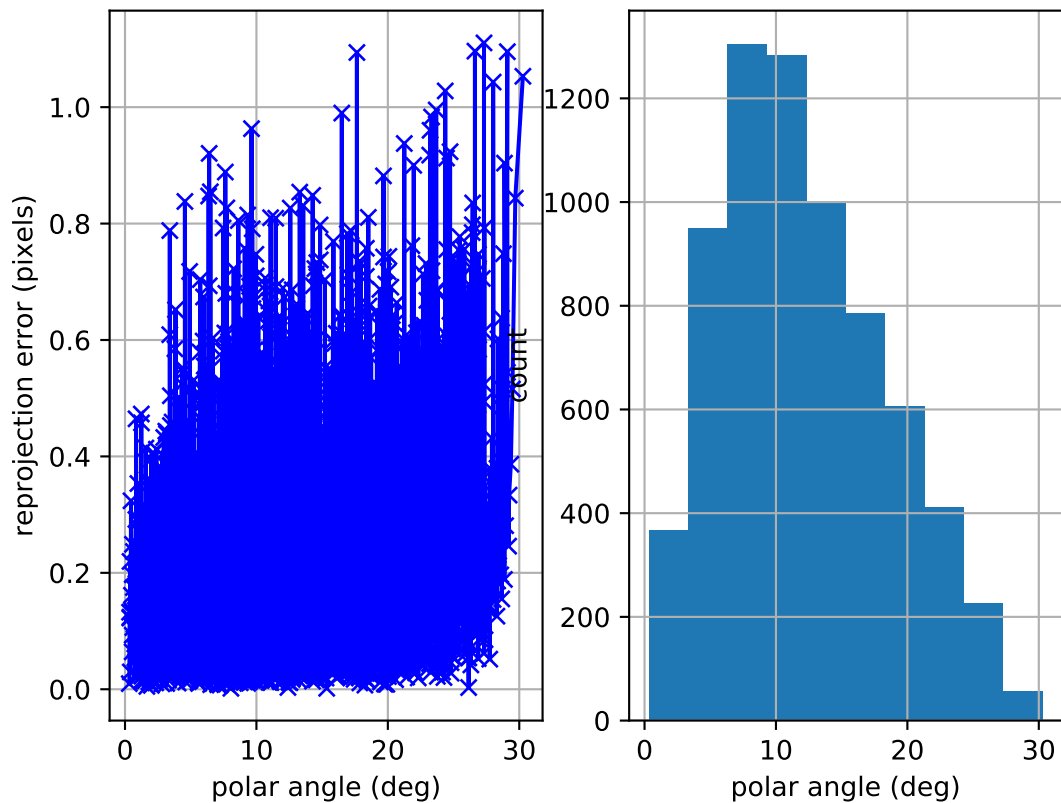
camera system



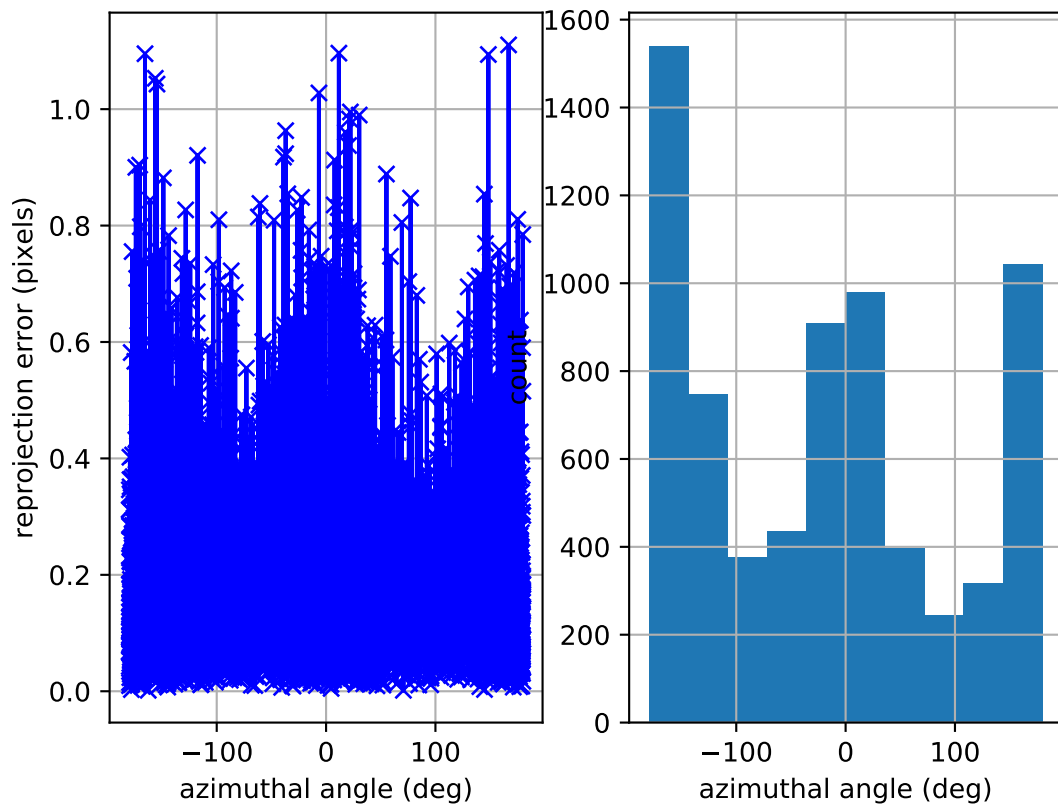
cam0: estimated poses



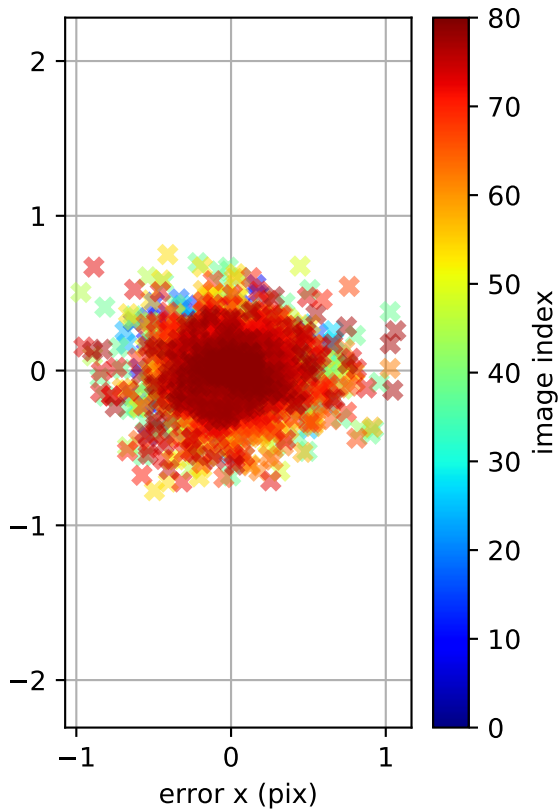
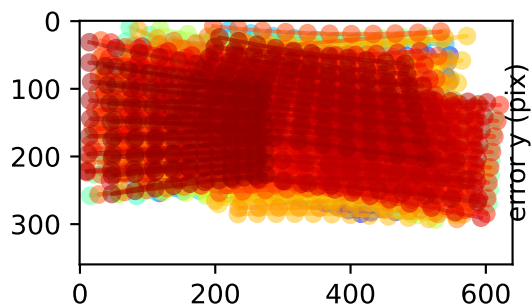
cam0: polar error



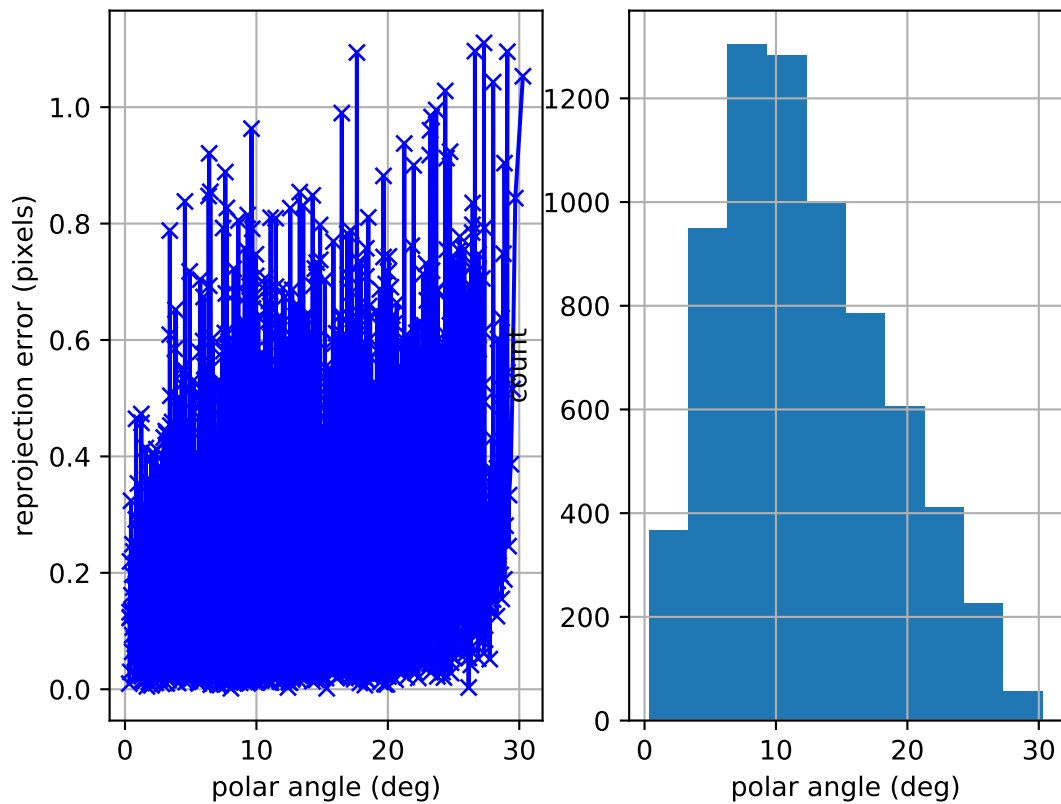
cam0: azimuthal error



cam0: reprojection errors

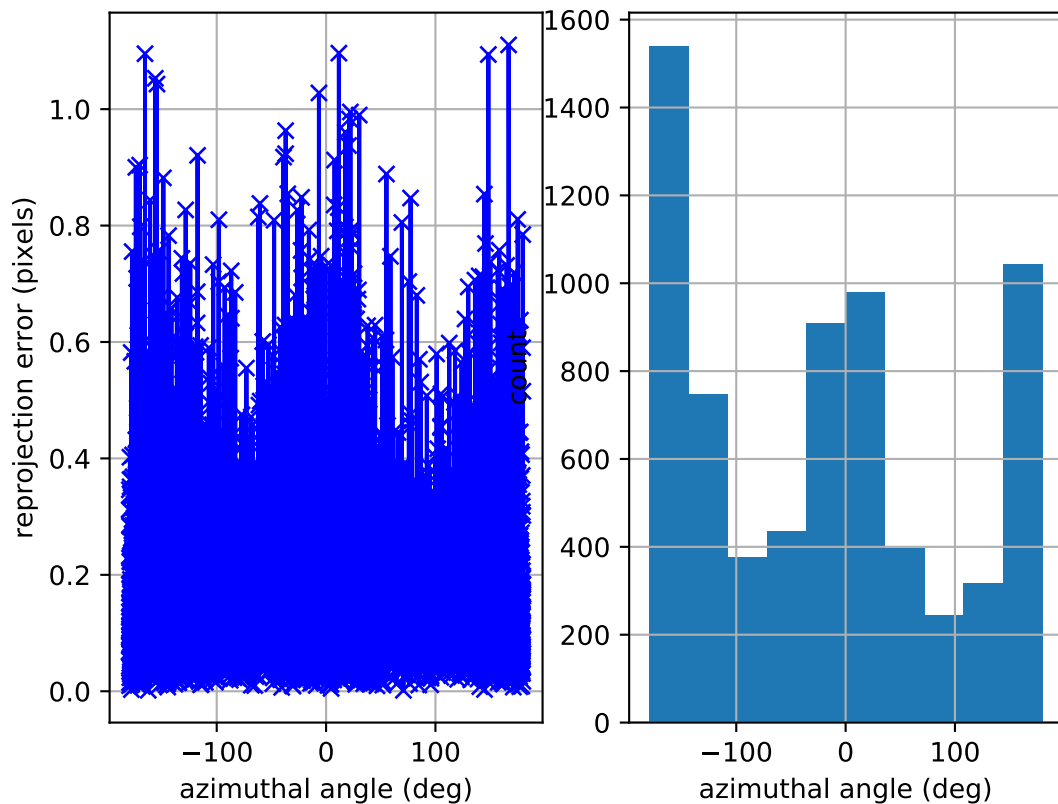


cam1: polar error

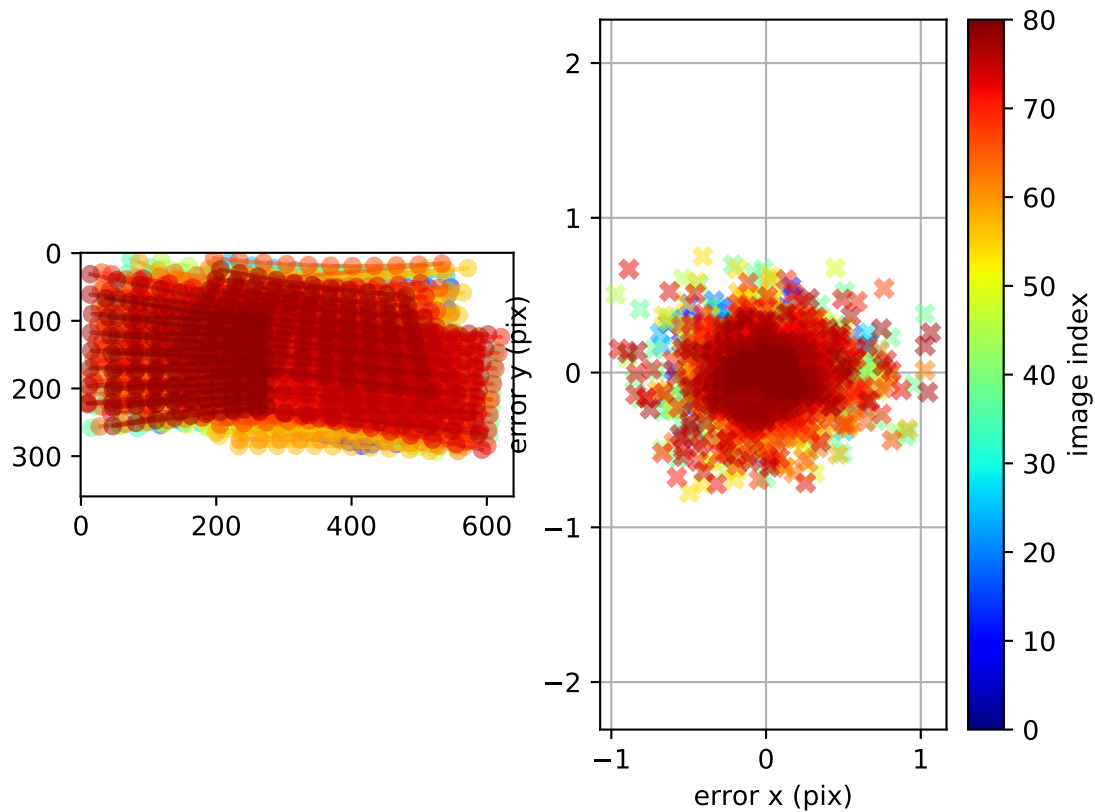




cam1: azimuthal error



cam1: reprojection errors



# Location of removed outlier corners

