

## Calibration results

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### Camera-system parameters:

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

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

distortion: [-0.25654653 0.19727457 -0.00043343 0.00499067] +- [ 0.0038832 0.00958461 0.00033668 0.00040419]

projection: [ 516.34979458 515.4755545 333.06919394 182.05340222] +- [ 0.28194611 0.30172785 1.19779155 0.4898362 ]

reprojection error: [-0.000150, -0.000247] +- [0.168057, 0.129107]

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

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

distortion: [-0.25058608 0.15353445 -0.00099968 0.00444158] +- [ 0.00340251 0.00687297 0.00032041 0.00033306]

projection: [ 517.27631413 516.37637782 333.55095986 181.14656536] +- [ 0.3177857 0.30733966 0.89128451 0.49119148]

reprojection error: [-0.000144, -0.000246] +- [0.174012, 0.132486]

### baseline T\_1\_0:

q: [ 0.00123868 -0.00242795 -0.00026349 0.99999625] +- [ 0.00190194 0.0040302 0.00016711]

t: [-0.63061786 -0.00001942 -0.00697495] +- [ 0.00076524 0.00067153 0.0035155 ]

## Target configuration

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Type: checkerboard

Rows

Count: 8

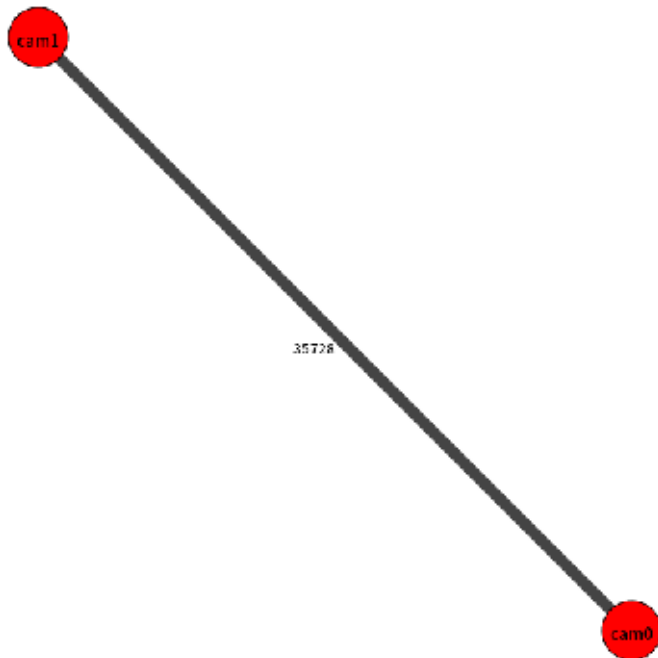
Distance: 0.15 [m]

Cols

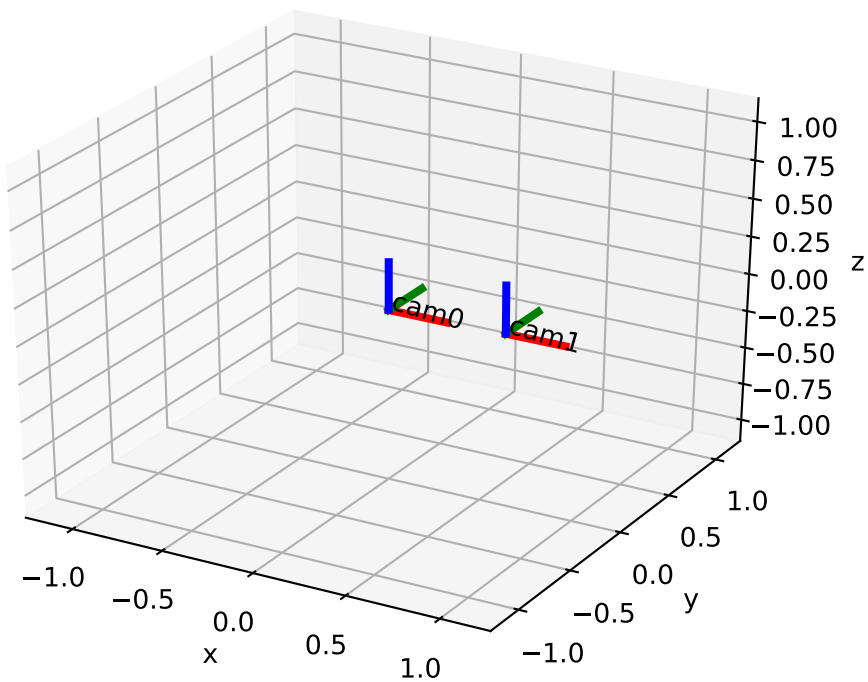
Count: 11

Distance: 0.15 [m]

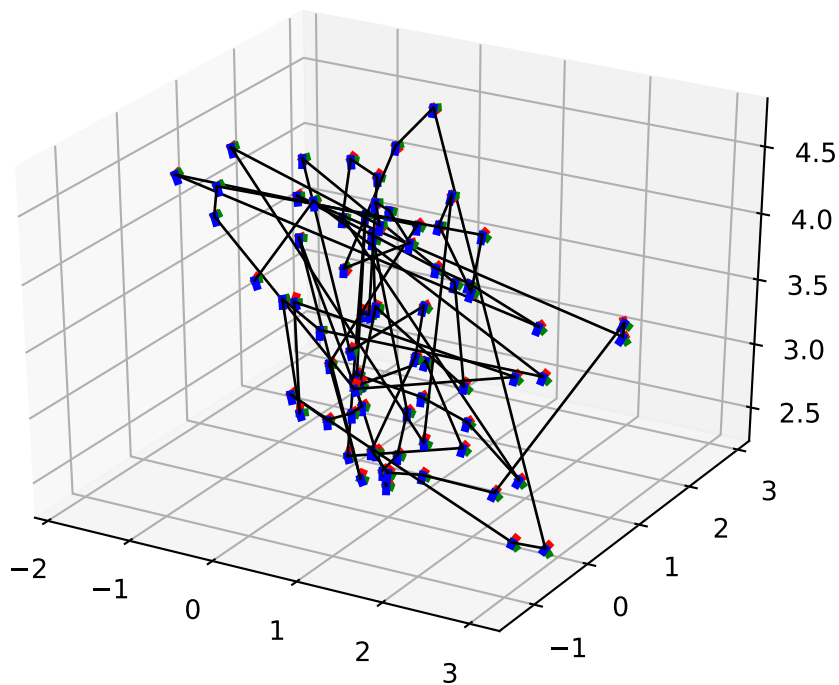
Inter-camera observations graph (edge weight=#mutual obs.)



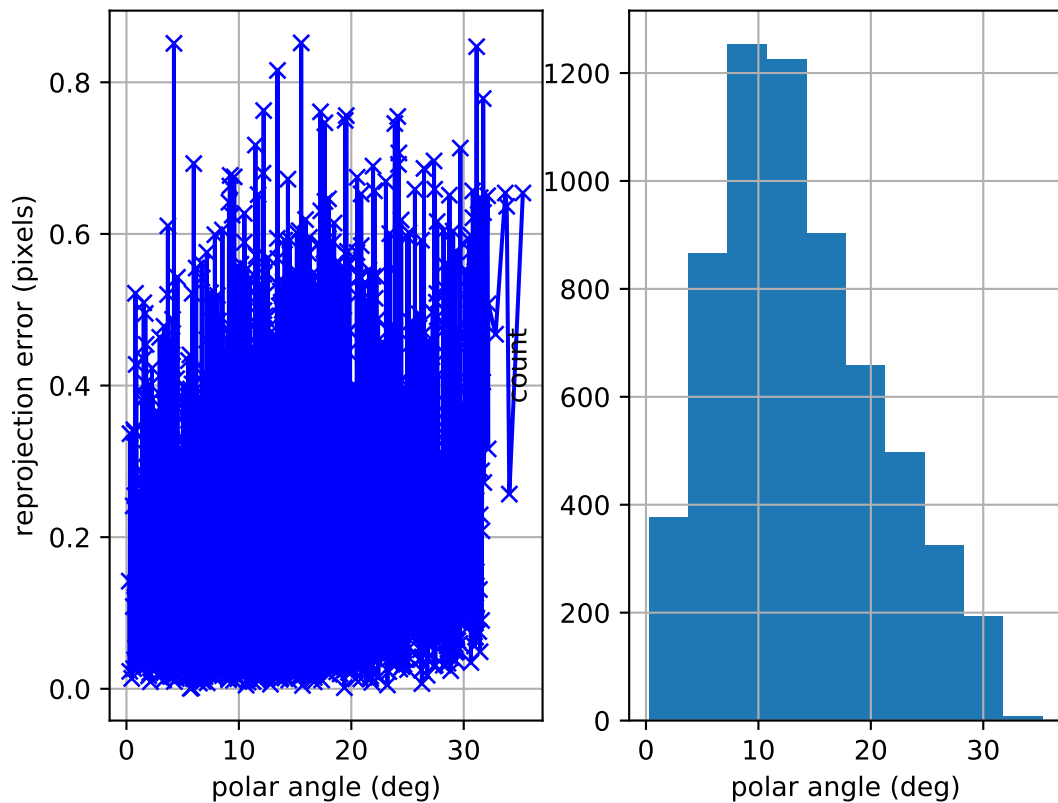
camera system



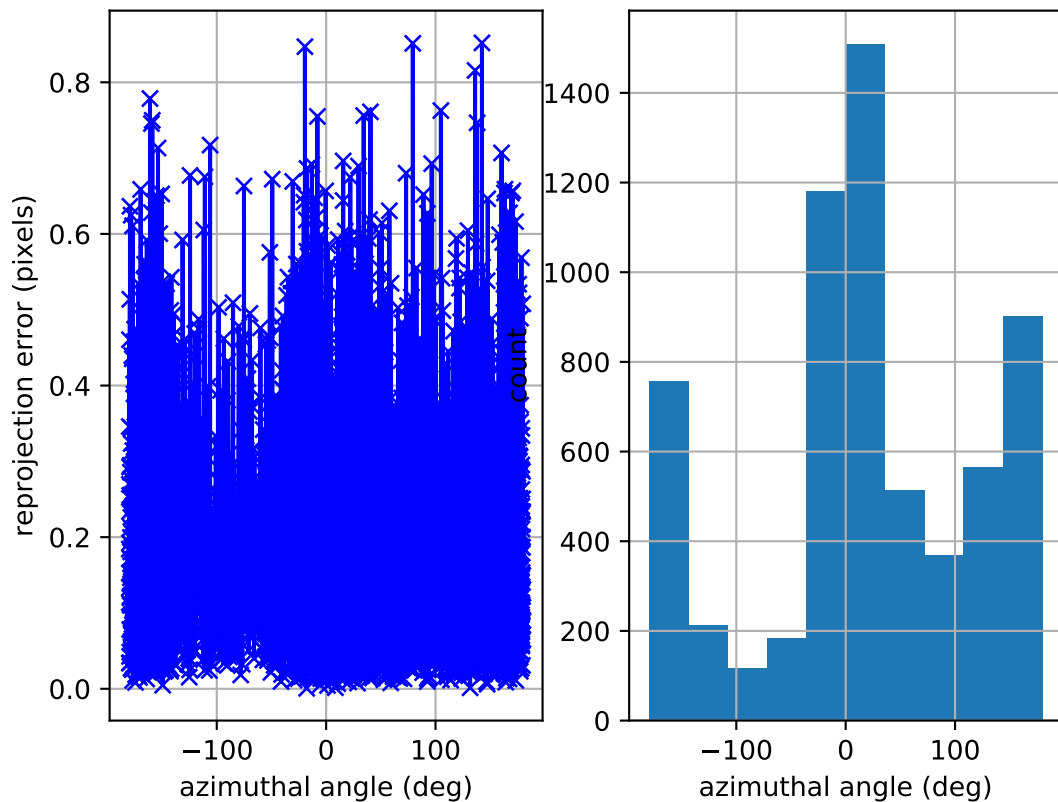
cam0: estimated poses



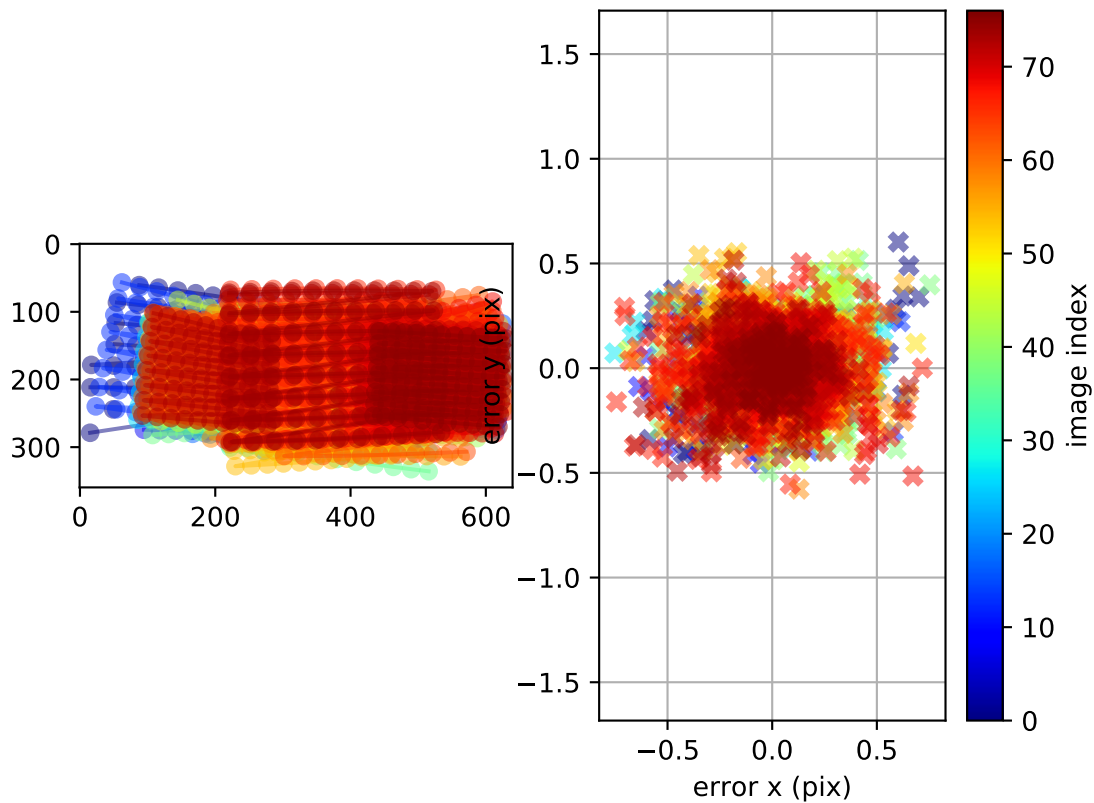
cam0: polar error



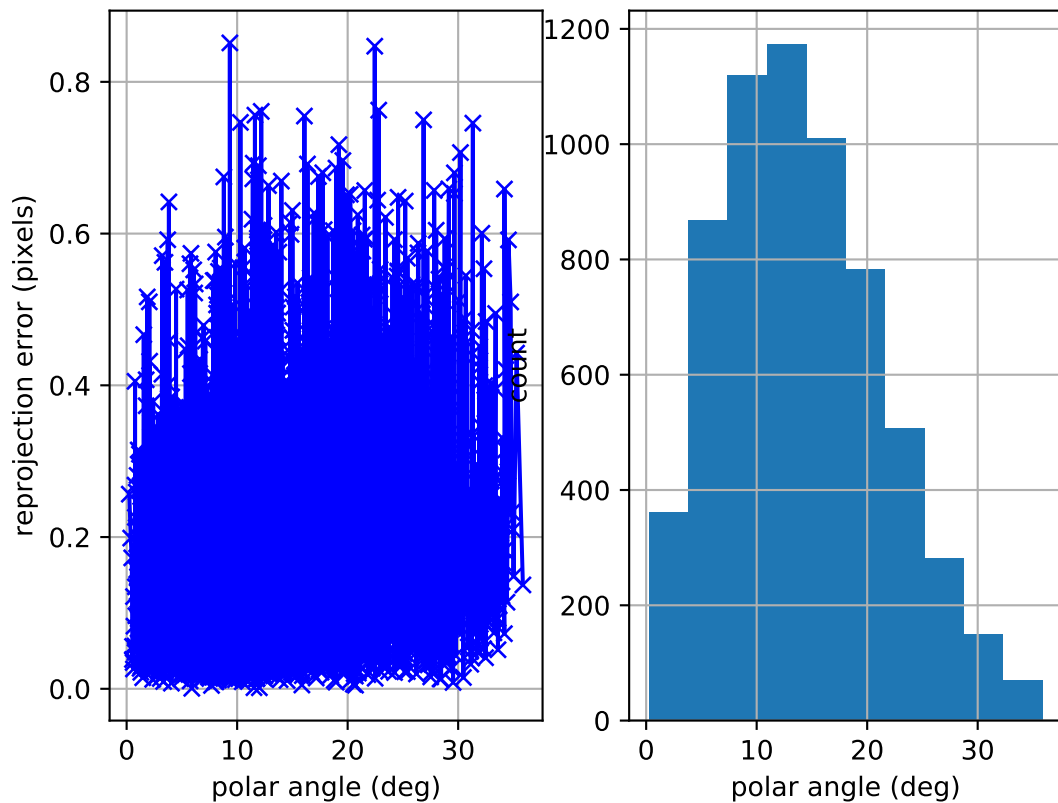
cam0: azimuthal error



cam0: reprojection errors

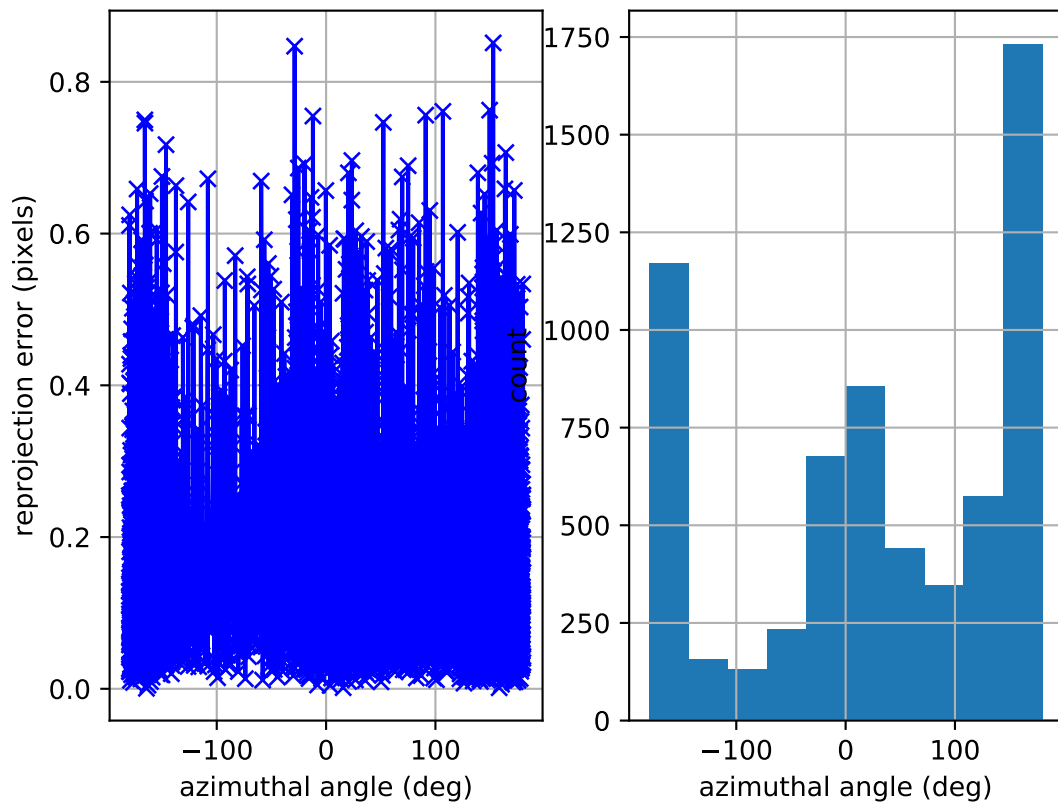


cam1: polar error

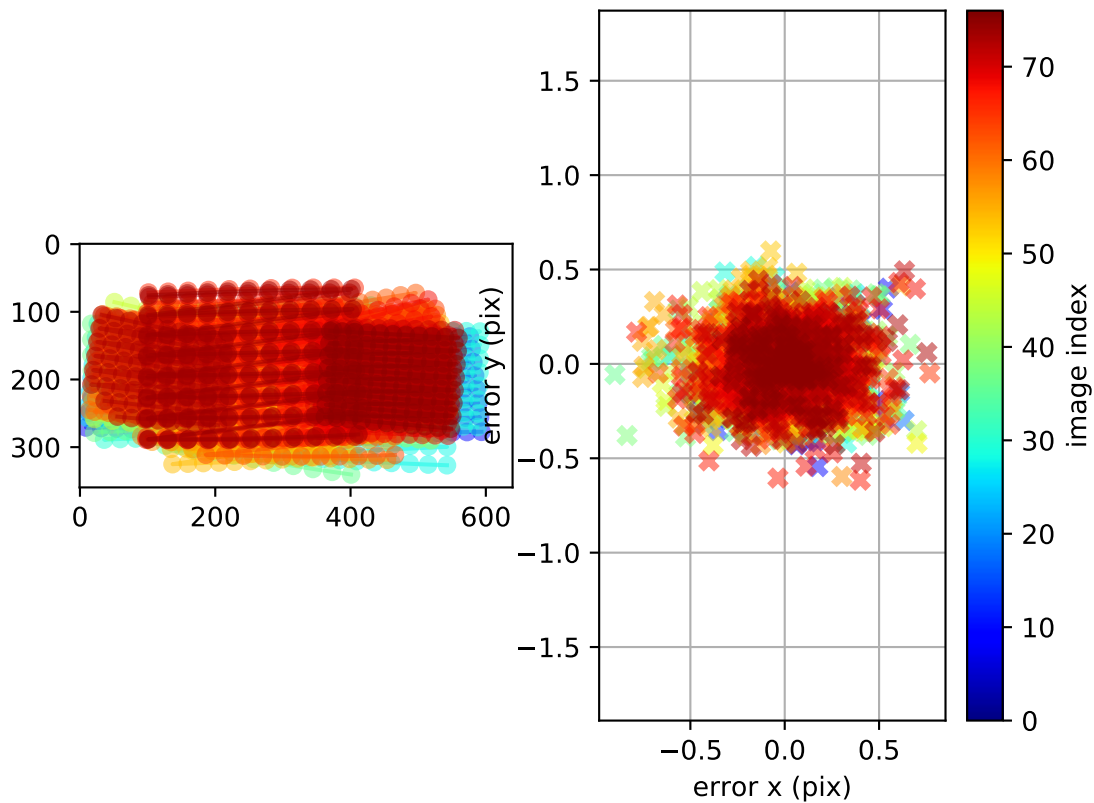




cam1: azimuthal error



cam1: reprojection errors



## Location of removed outlier corners

