

## Calibration results

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### Camera-system parameters:

cam0 (/left/image\_raw):

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

distortion: [-0.22928116 0.06878711 0.00009283 0.00039086] +- [0.00029226 0.00023175 0.00007613 0.00007175]

projection: [913.55593 915.66942085 772.48588631 579.94937864] +- [0.12062485 0.12465355 0.42884614 0.43361907]

reprojection error: [-0.000050, -0.000020] +- [0.495410, 0.405512]

cam1 (/center/image\_raw):

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

distortion: [-0.2343535 0.07398191 0.00004125 0.0000892] +- [0.00031768 0.00027932 0.00007868 0.00006582]

projection: [915.39797341 917.09499666 777.5470411 567.39055462] +- [0.10195134 0.1081262 0.38803298 0.43573455]

reprojection error: [-0.000023, -0.000026] +- [0.485539, 0.401122]

cam2 (/right/image\_raw):

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

distortion: [-0.23628778 0.07612523 0.00002559 0.00007312] +- [0.00034552 0.00032241 0.000073 0.00008568]

projection: [919.52111239 921.14505629 776.54832552 568.49414399] +- [0.12364076 0.1271847 0.47704249 0.4377385]

reprojection error: [-0.000028, 0.000001] +- [0.473318, 0.390769]

### baseline T\_1\_0:

q: [-0.00114086 -0.00918466 0.00317523 0.99995213] +- [0.00022869 0.00037923 0.00004905]

t: [-0.39032204 -0.00137394 -0.00990071] +- [0.00009976 0.00008243 0.00025069]

### baseline T\_2\_1:

q: [0.02577375 0.00654603 -0.00651617 0.99962513] +- [0.00027211 0.00044375 0.00007065]

t: [-0.62210612 -0.00666152 -0.01113677] +- [0.00011718 0.00008337 0.00033549]

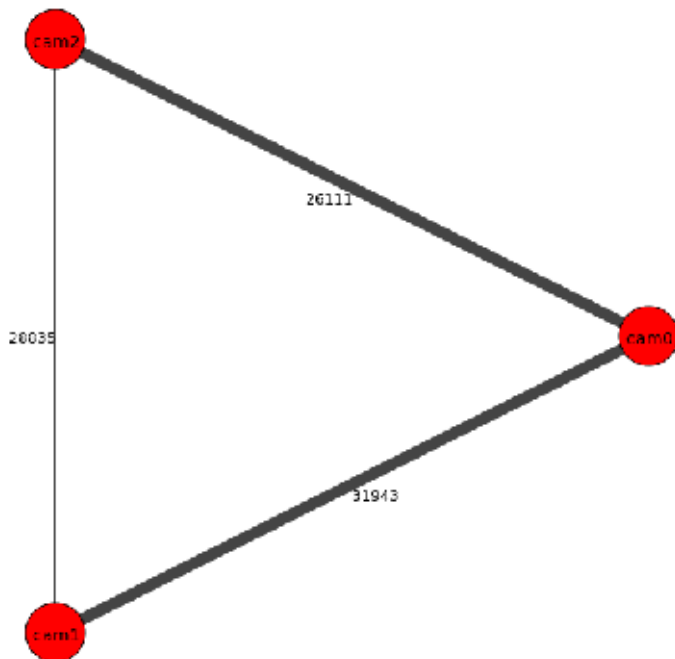
## Target configuration

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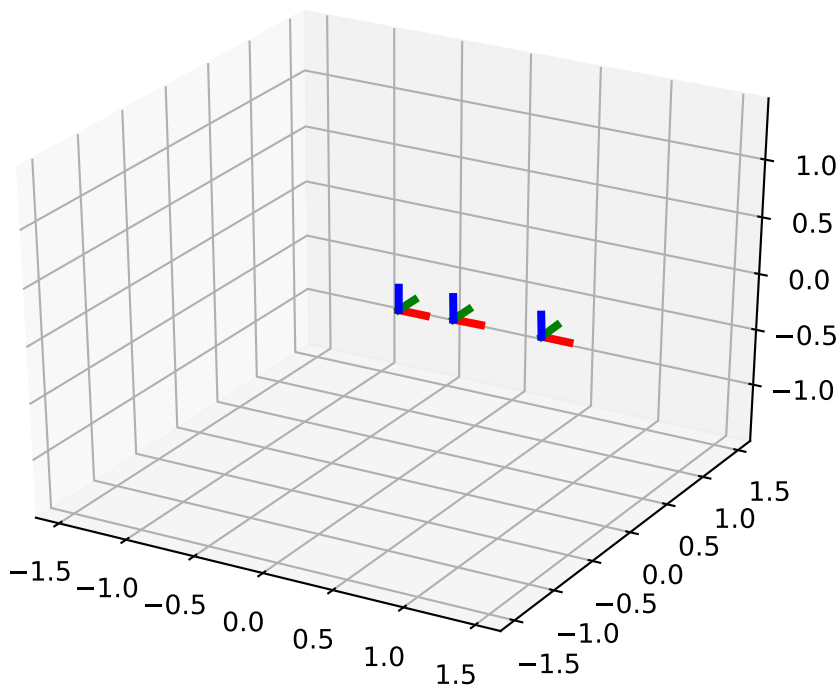
Type: aprilgrid

Tags:  
Rows: 6  
Cols: 6  
Size: 0.099 [m]  
Spacing 0.0299999997 [m]

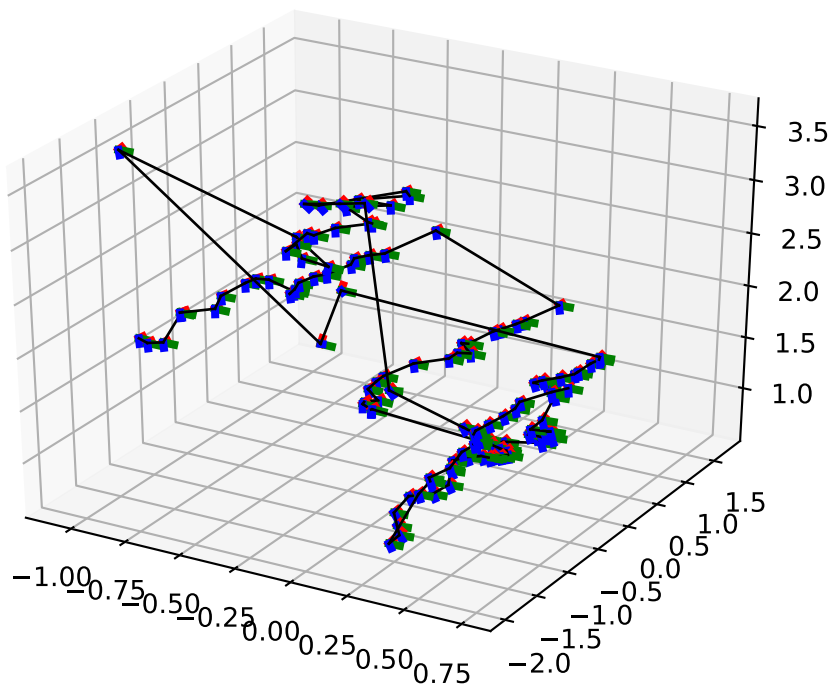
Inter-camera observations graph (edge weight=#mutual obs.)



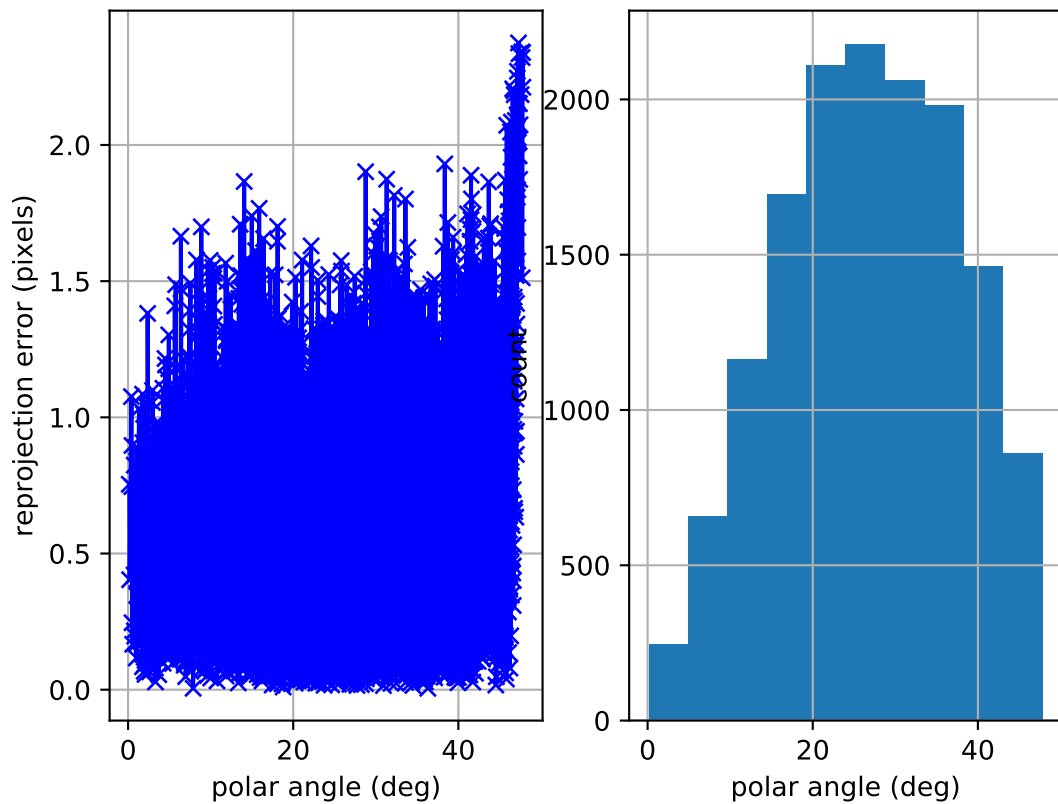
camera system



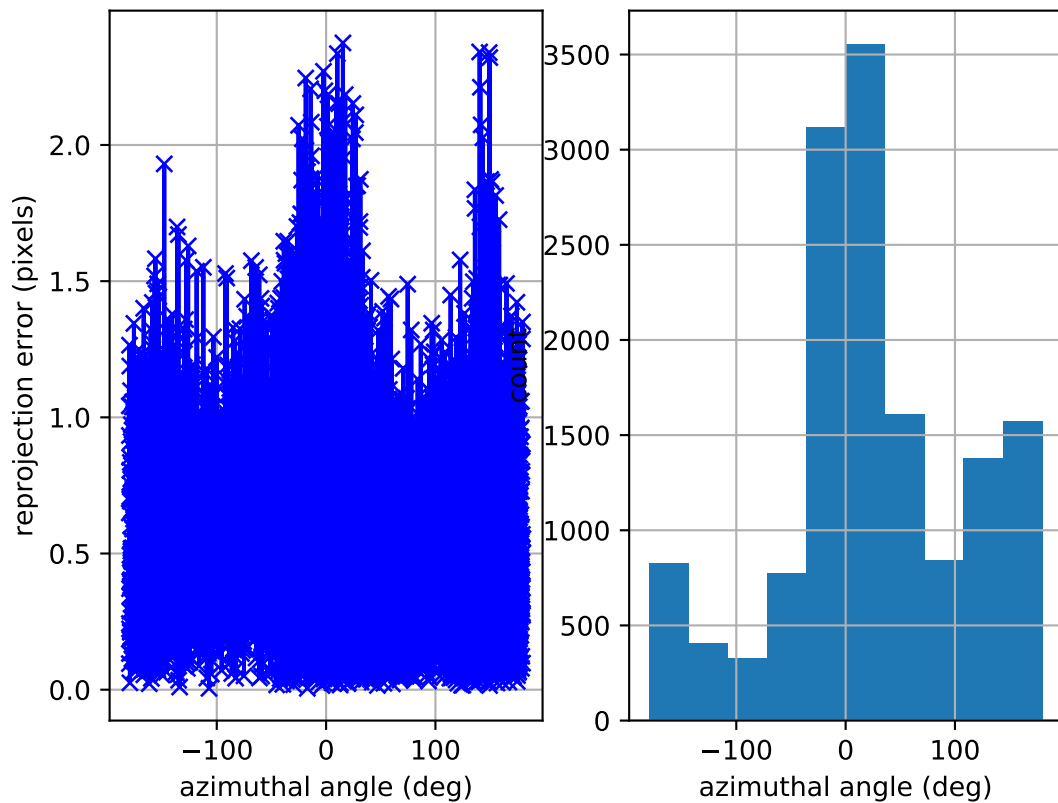
cam0: estimated poses



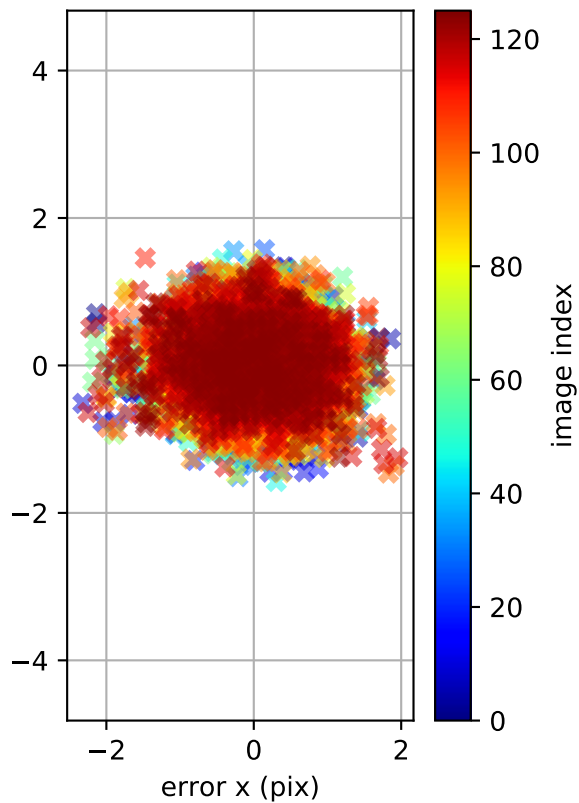
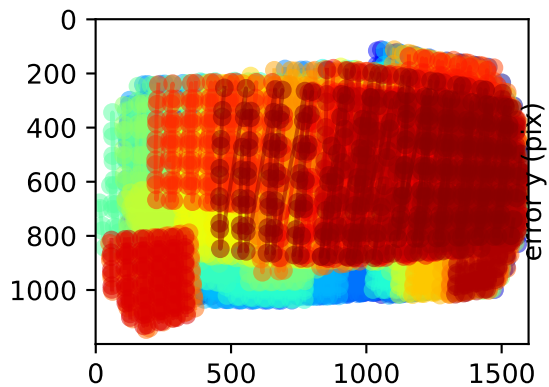
cam0: polar error



cam0: azimuthal error

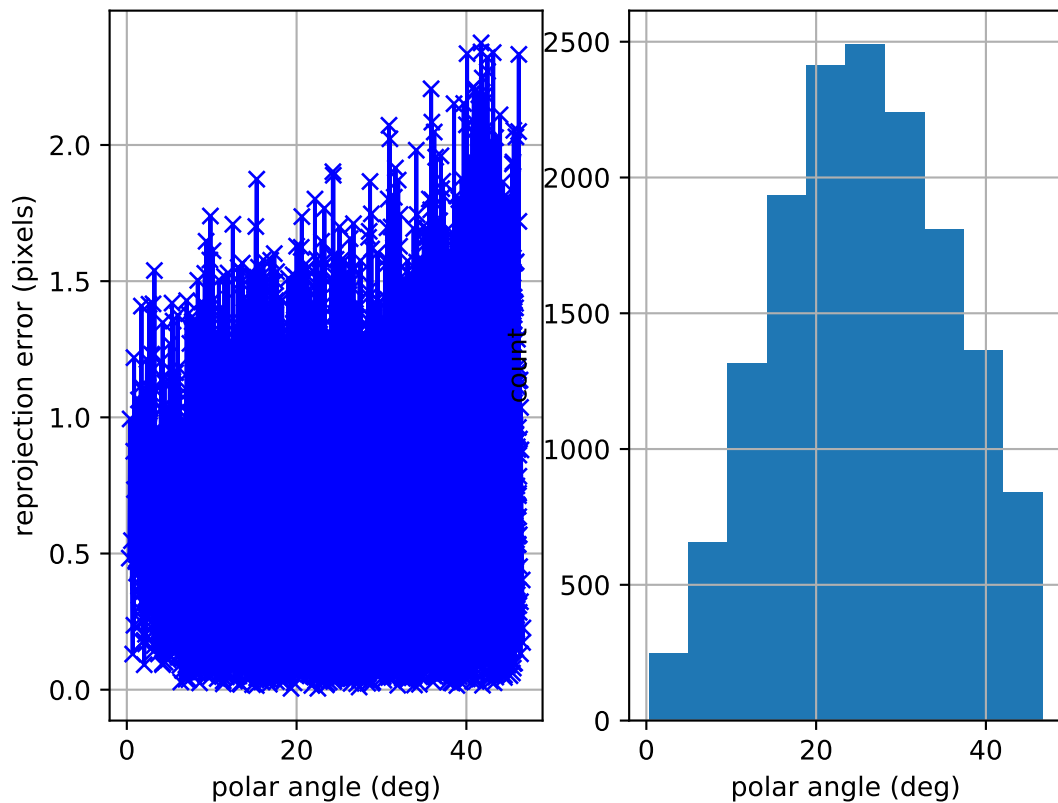


cam0: reprojection errors

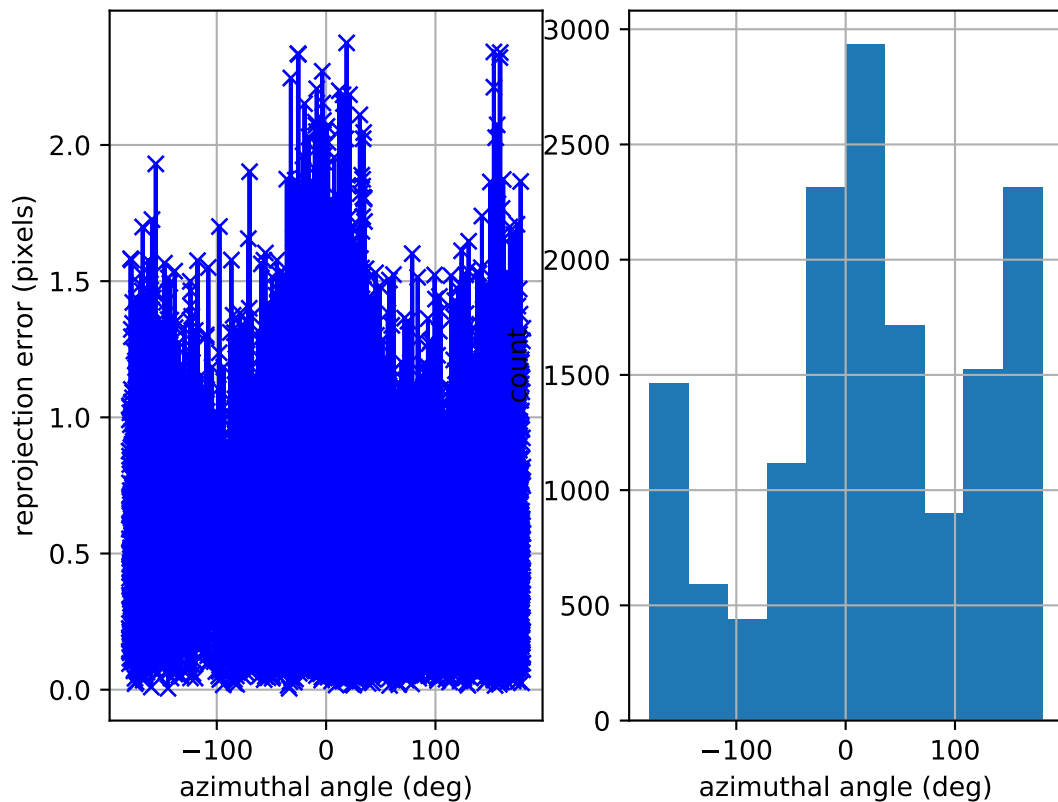




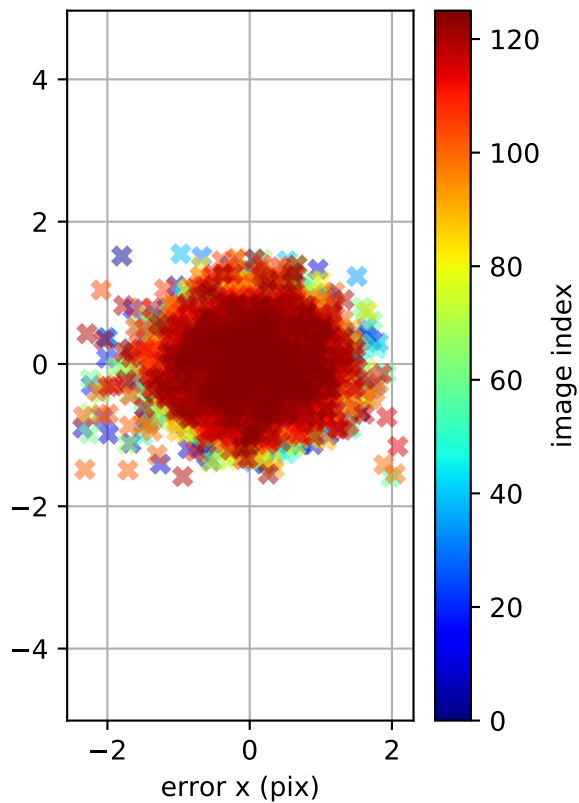
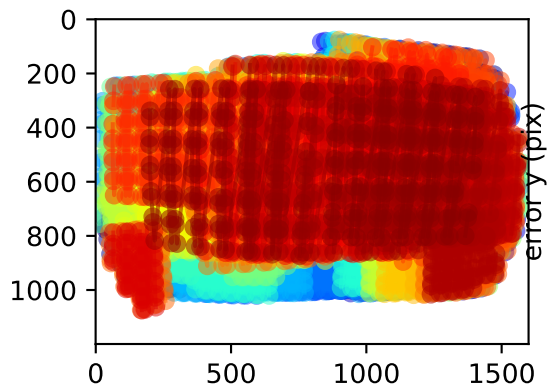
cam1: polar error



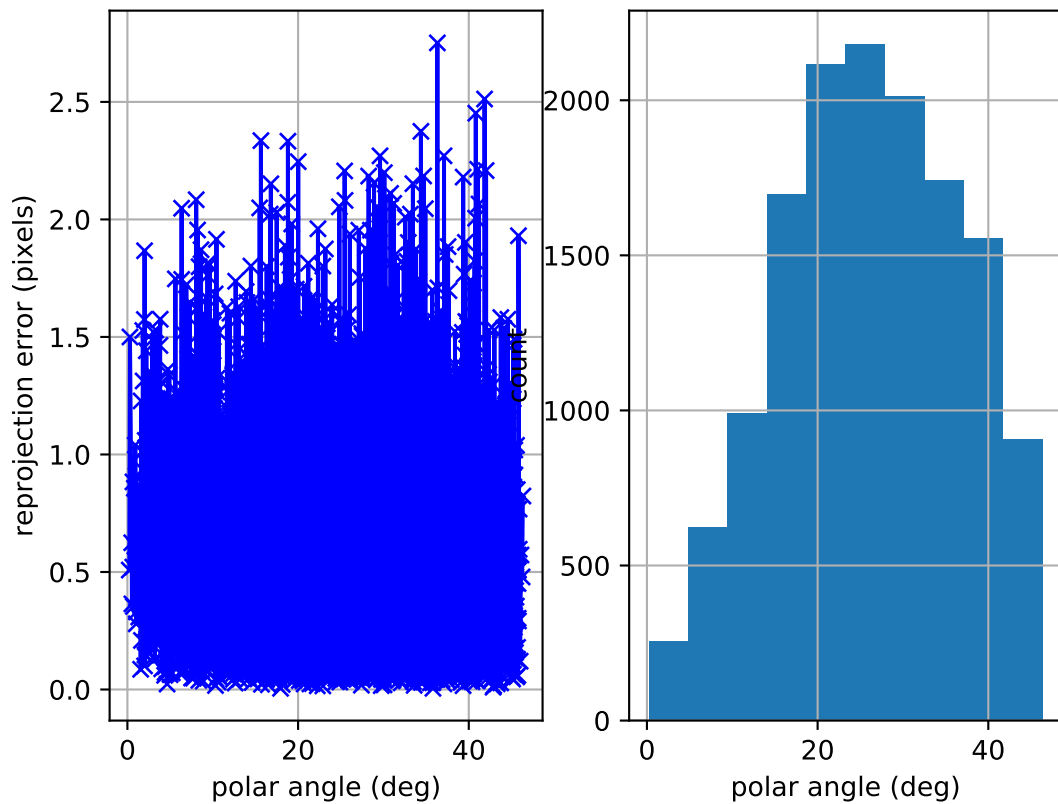
cam1: azimuthal error



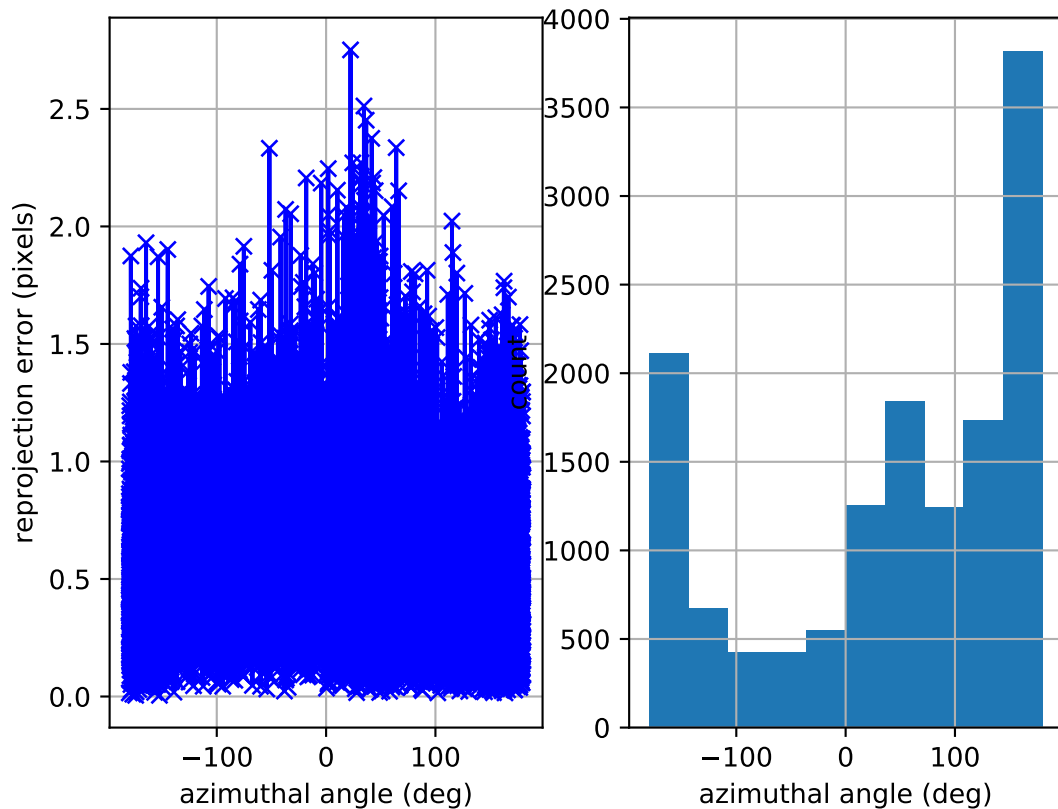
cam1: reprojection errors



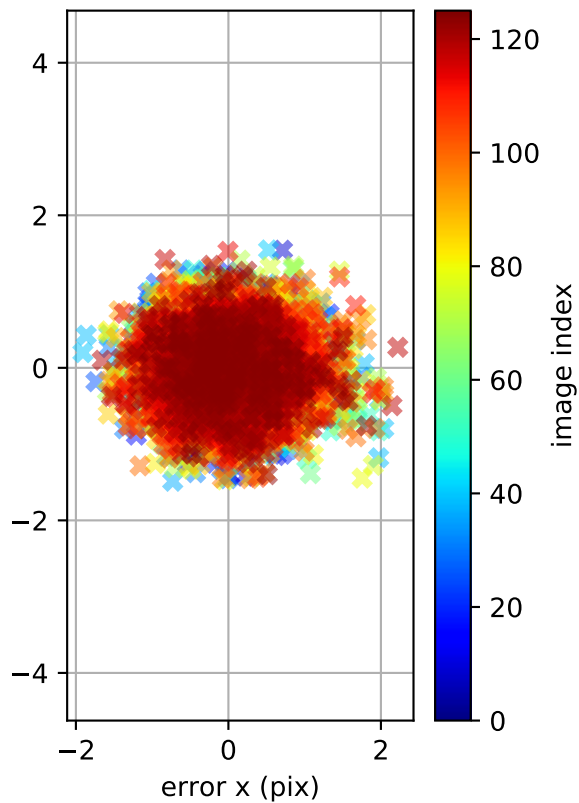
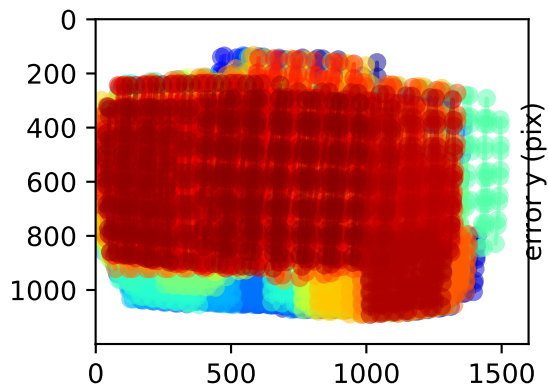
cam2: polar error



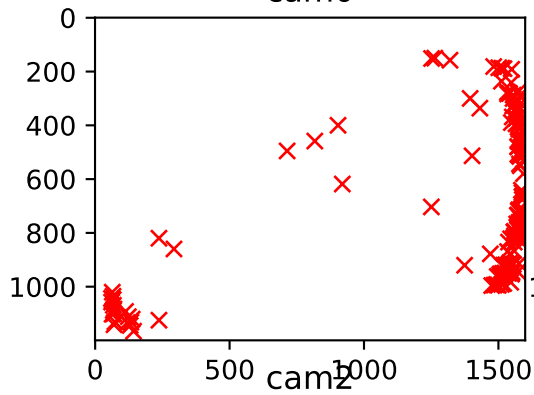
cam2: azimuthal error



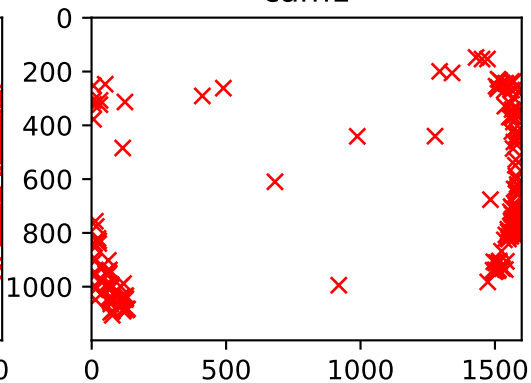
## cam2: reprojection errors



## cam0



cam1



cam20

