

## Calibration results

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### Camera-system parameters:

cam0 (/t265/fisheye1/image\_raw):

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

distortion: [-0.00770273 0.05645265 -0.05420016 0.01160013] +- [0.00260536 0.00597988 0.0050449 0.00145058]

projection: [280.04528976 279.13548477 422.57618597 398.21085361] +- [0.01832942 0.01883234 0.11503617 0.11832673]

reprojection error: [-0.000000, -0.000000] +- [0.496539, 0.520906]

cam1 (/t265/fisheye2/image\_raw):

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

distortion: [ 0.00368163 0.03279753 -0.03578695 0.00706684] +- [0.00273667 0.00645608 0.0055791 0.0016338 ]

projection: [280.1113365 278.95813286 422.79671065 397.11143503] +- [0.01802407 0.01878333 0.11188047 0.11760618]

reprojection error: [0.000000, -0.000000] +- [0.501071, 0.534379]

baseline T\_1\_0:

q: [-0.002754 0.00289859 0.00108536 0.99999142] +- [0.00040956 0.00047272 0.00008798]

t: [-0.06233999 0.00001706 -0.00013432] +- [0.00008729 0.00010076 0.00020069]

## Target configuration

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Type: aprilgrid

Tags:

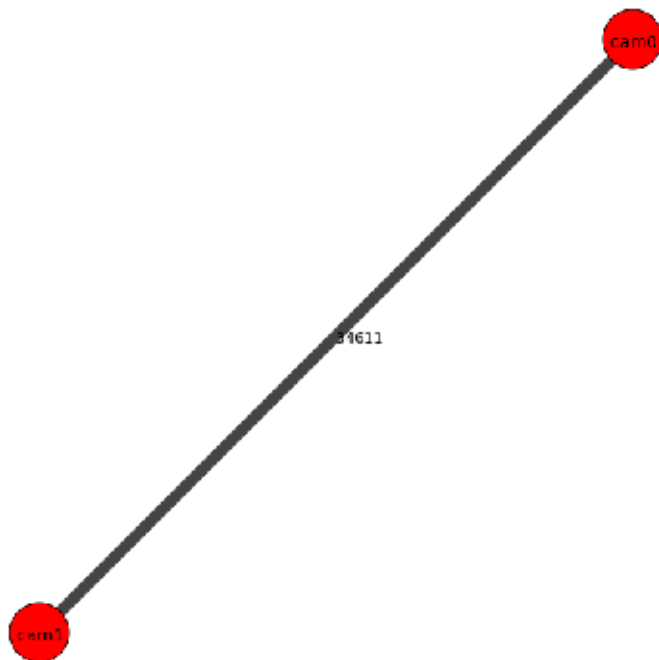
Rows: 6

Cols: 6

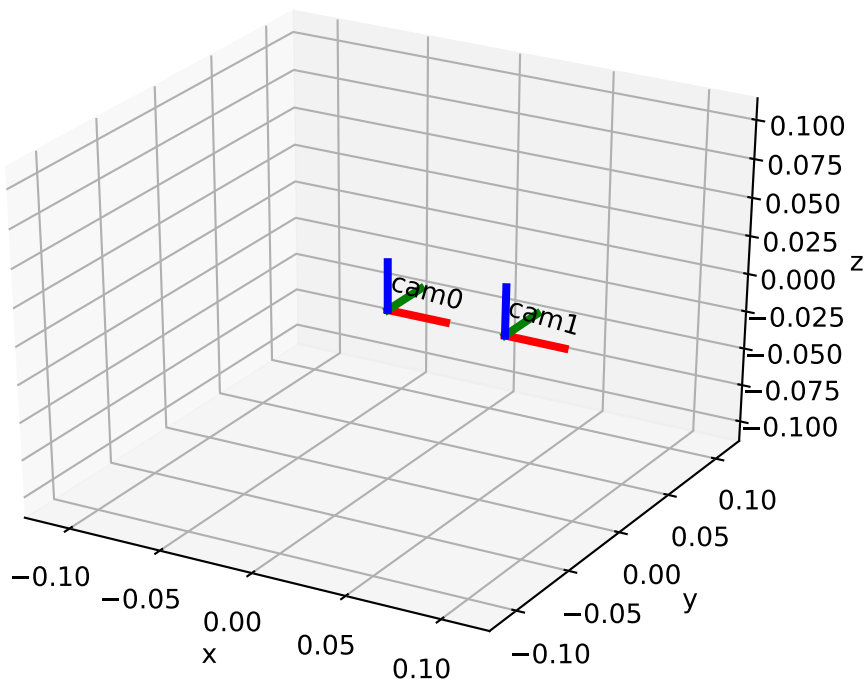
Size: 0.088 [m]

Spacing 0.026399999999999996 [m]

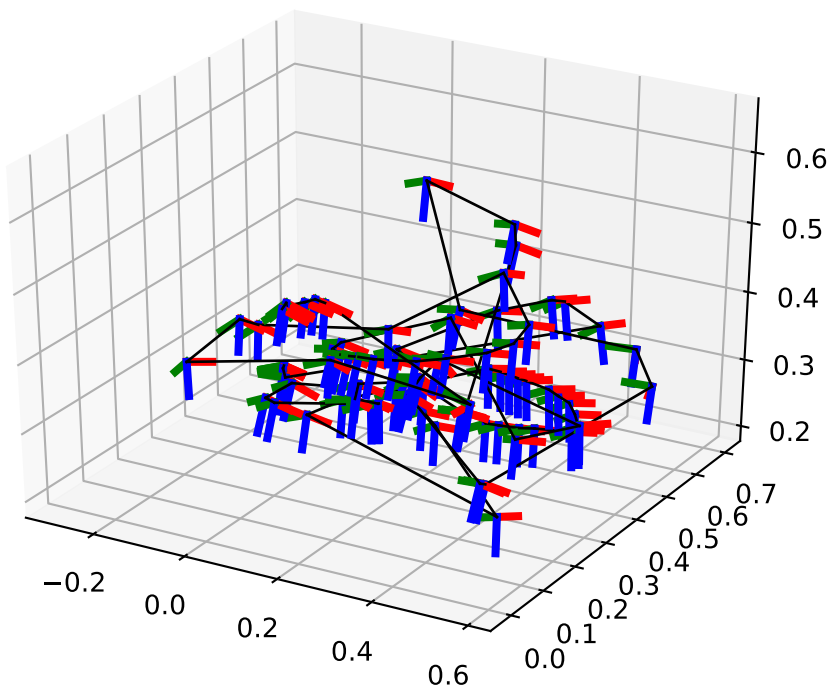
Inter-camera observations graph (edge weight=#mutual obs.)



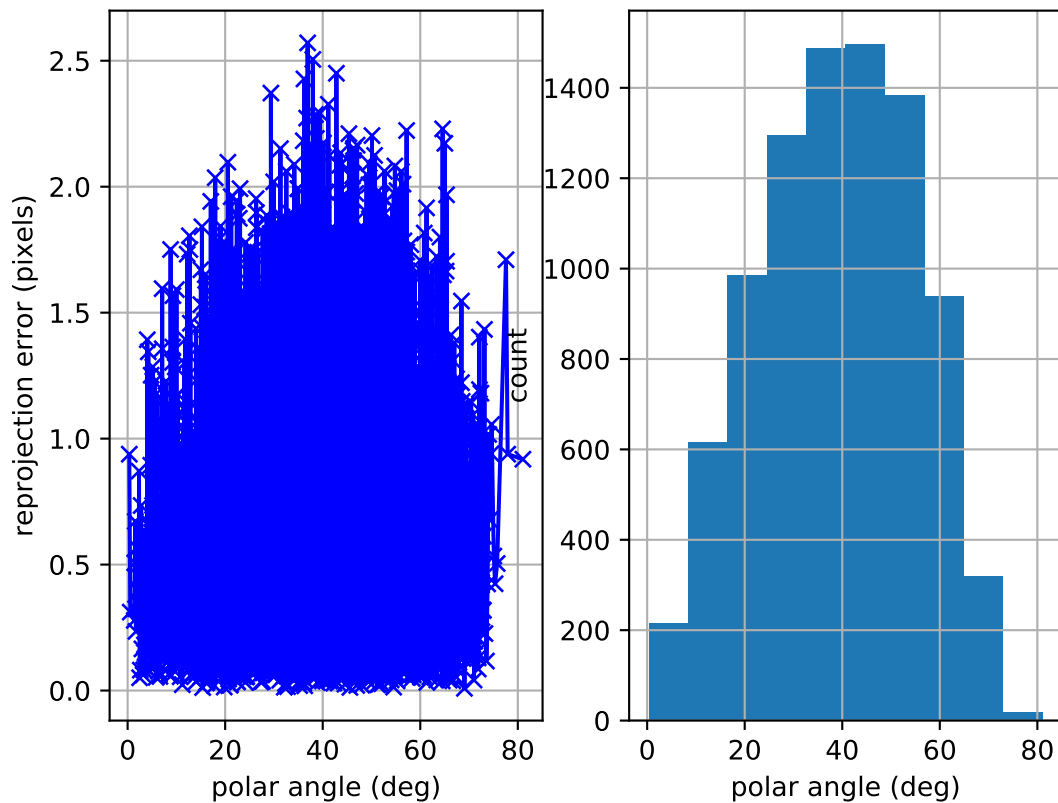
camera system



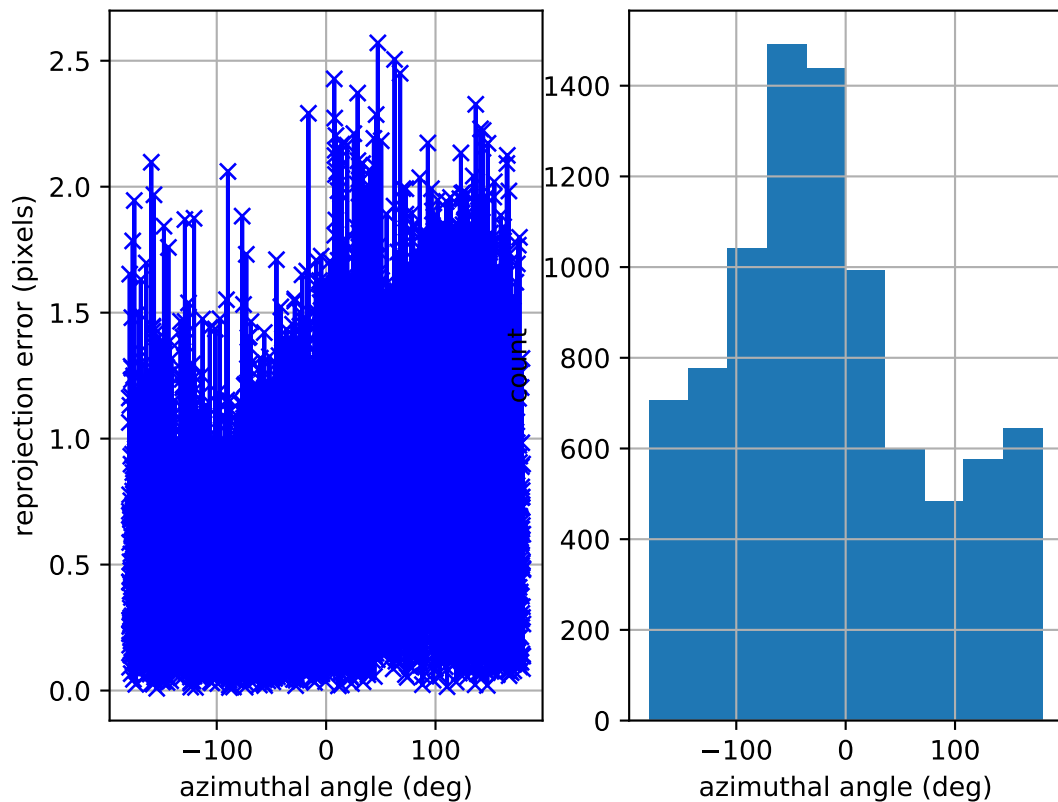
cam0: estimated poses



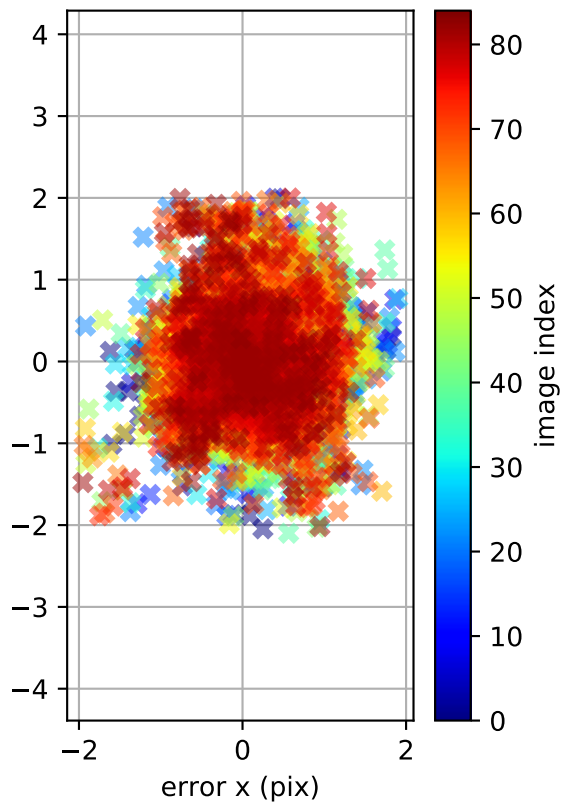
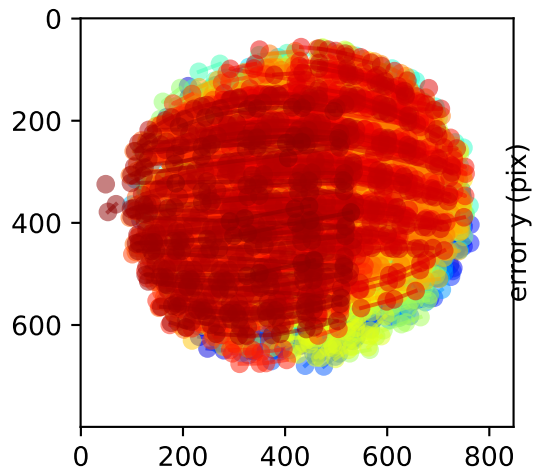
cam0: polar error



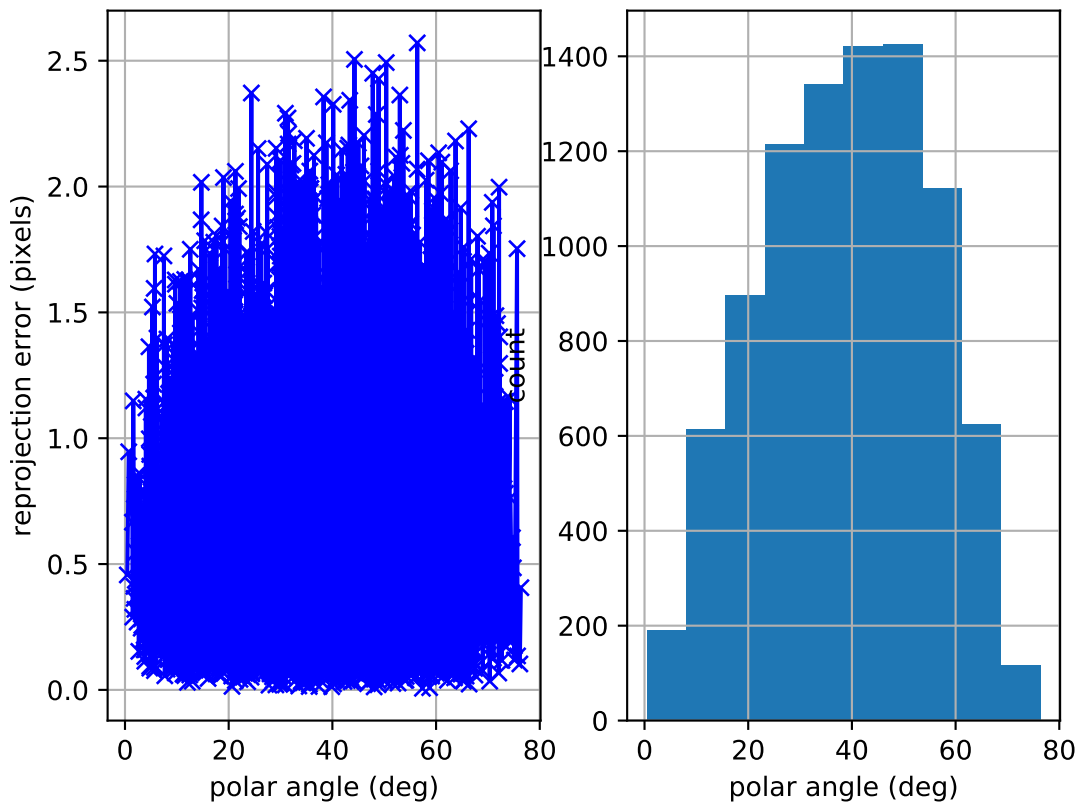
cam0: azimuthal error



cam0: reprojection errors

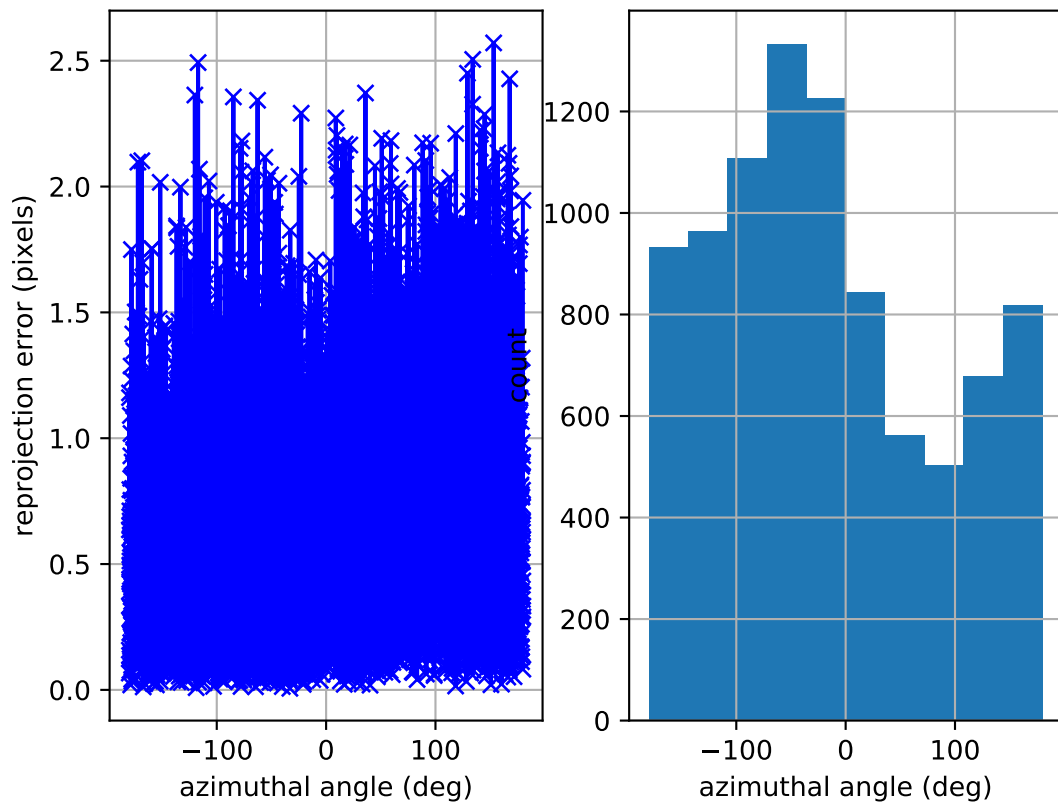


cam1: polar error

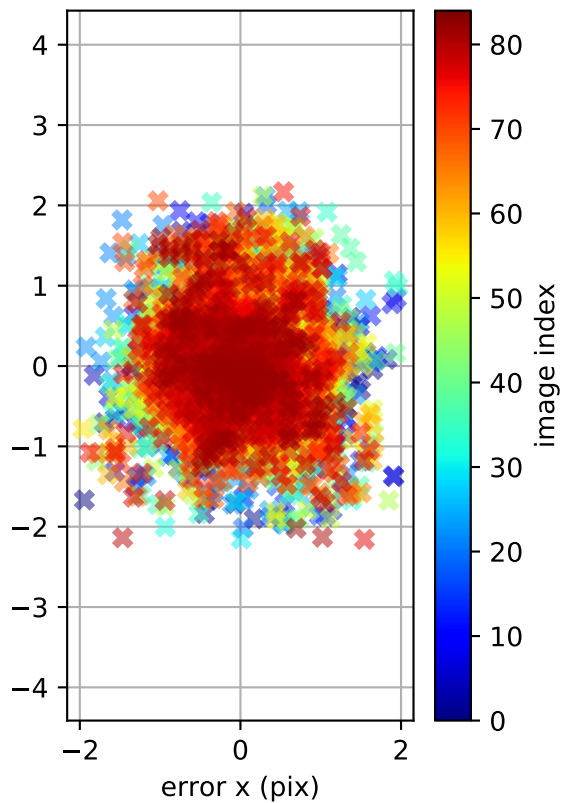
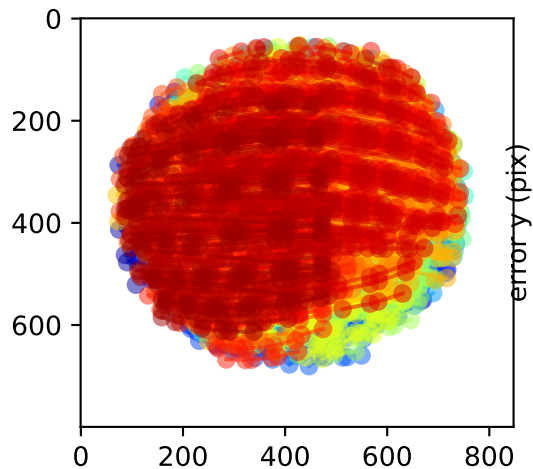




cam1: azimuthal error

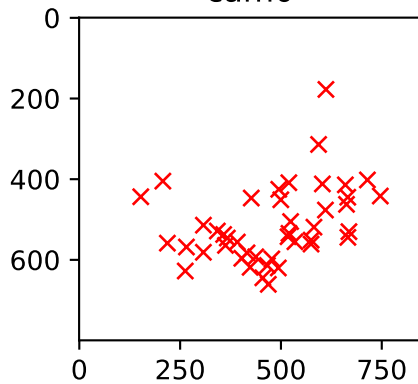


cam1: reprojection errors



# Location of removed outlier corners

cam0



cam1

