

## Calibration results

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### Camera-system parameters:

cam0 (/cam0/image\_raw):

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

distortion: [ 0.934547] +- [ 0.00400838]

projection: [ 268.40829687 269.14866171 316.47550604 200.89344484] +- [ 1.18104226 1.17605815 0.2888894 0.27019077]

reprojection error: [0.000001, -0.000001] +- [0.125268, 0.116970]

cam1 (/cam1/image\_raw):

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

distortion: [ 0.93194684] +- [ 0.00407765]

projection: [ 268.140164 268.86036097 315.89354202 199.97308698] +- [ 1.24245637 1.236826 0.3050856 0.27196676]

reprojection error: [-0.000002, 0.000001] +- [0.133318, 0.114211]

baseline T\_1\_0:

q: [-0.00220791 -0.00678 -0.01219819 0.99990018] +- [ 0.00071413 0.0011244 0.00014201]

t: [-0.08040919 0.00008563 0.00012344] +- [ 0.00013378 0.00011624 0.00038144]

### Target configuration

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Type: aprilgrid

Tags:

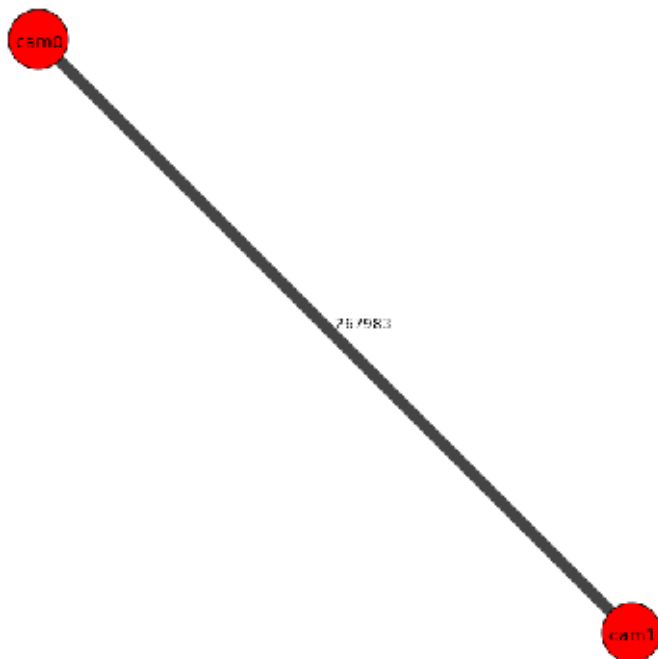
Rows: 6

Cols: 6

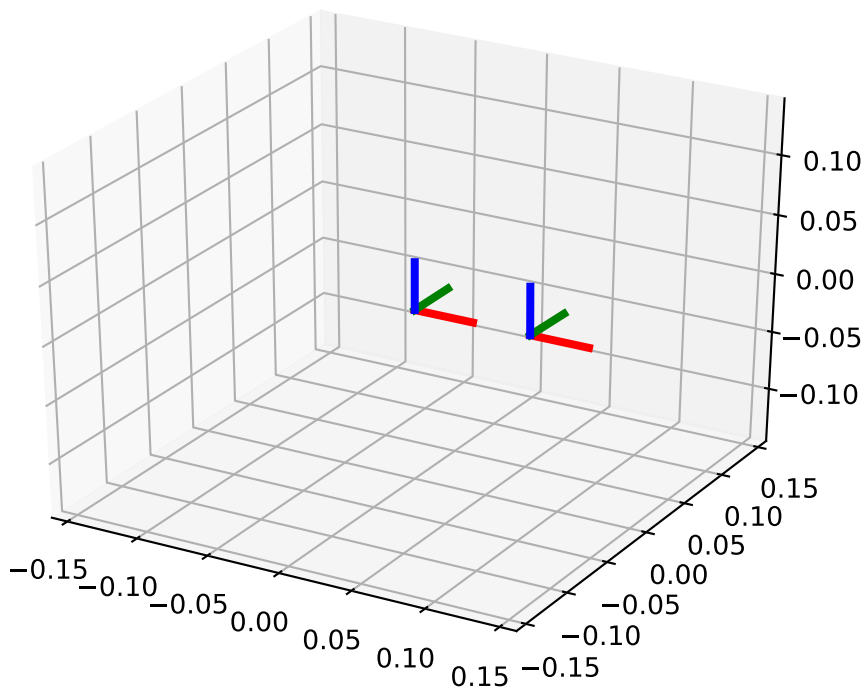
Size: 0.0312 [m]

Spacing 0.00959999976 [m]

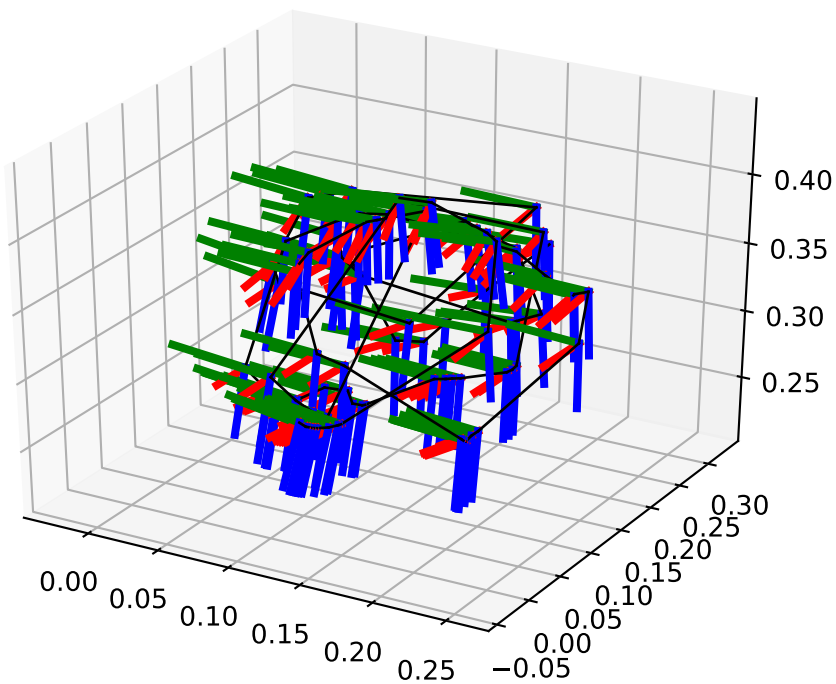
Inter-camera observations graph (edge weight=#mutual obs.)



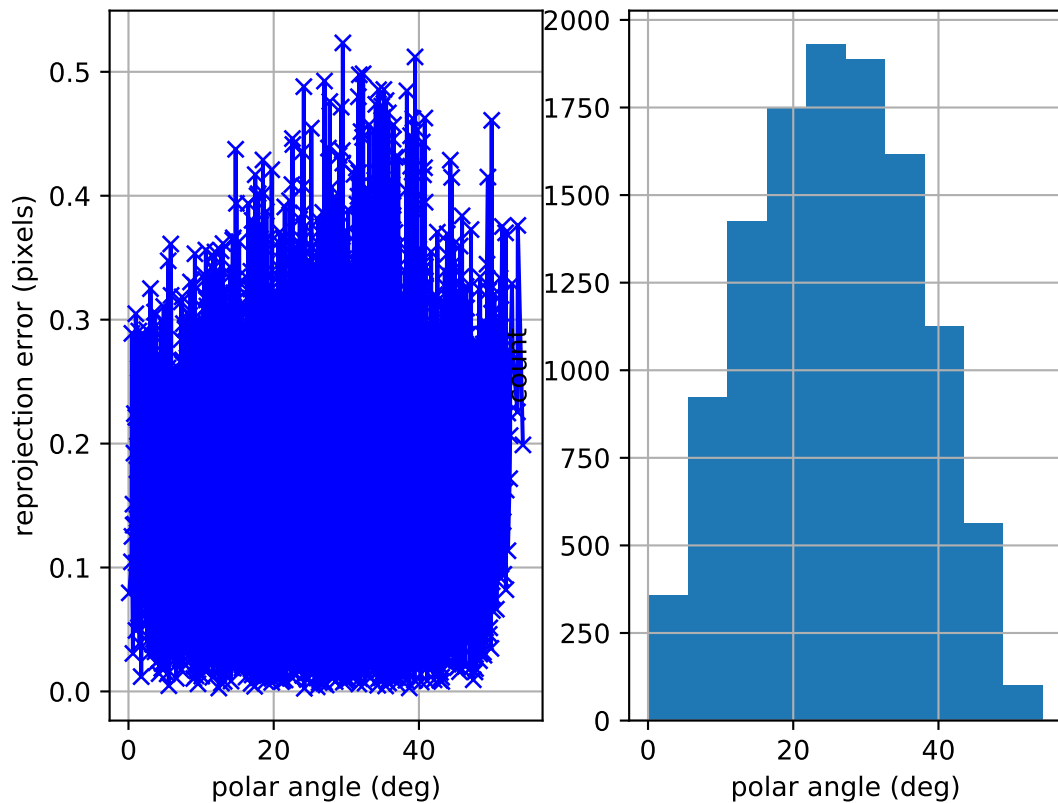
camera system



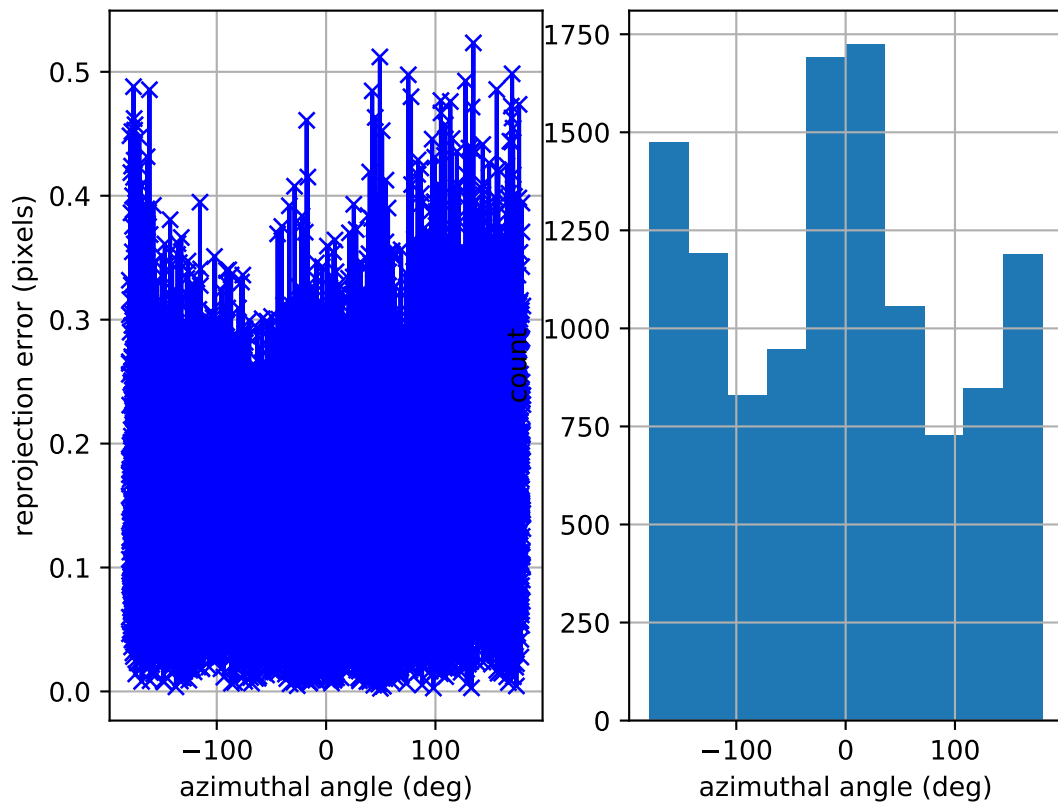
cam0: estimated poses



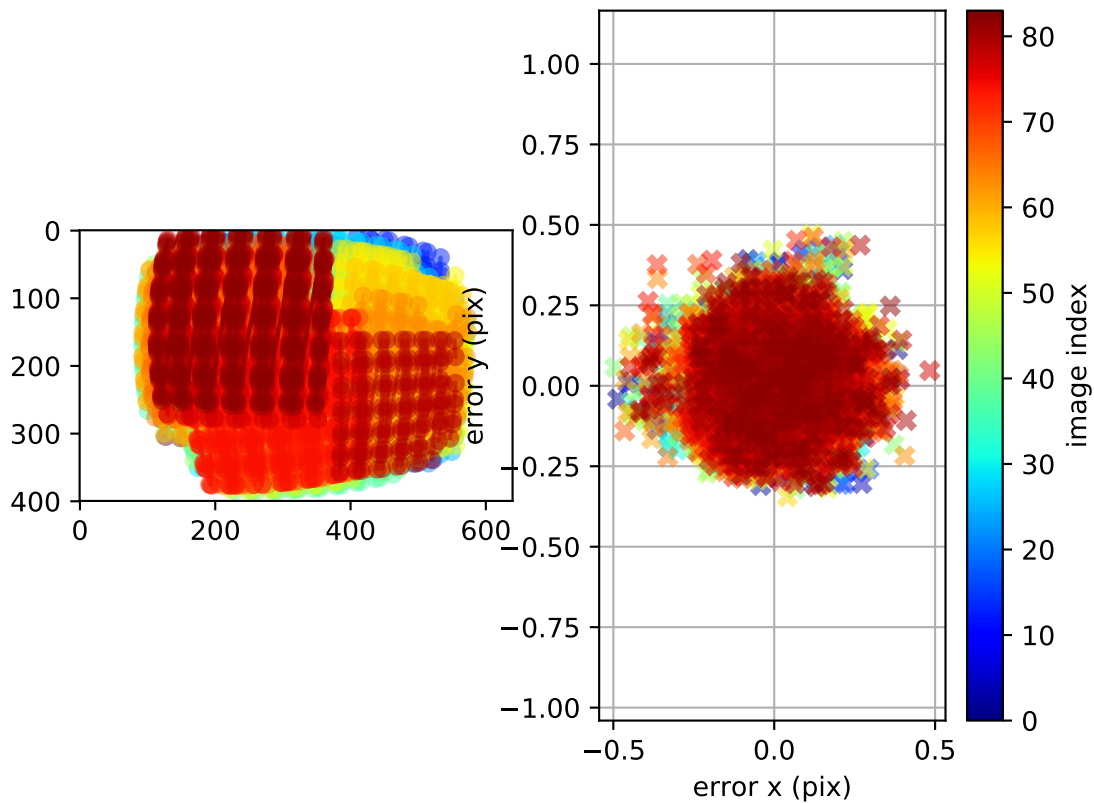
cam0: polar error



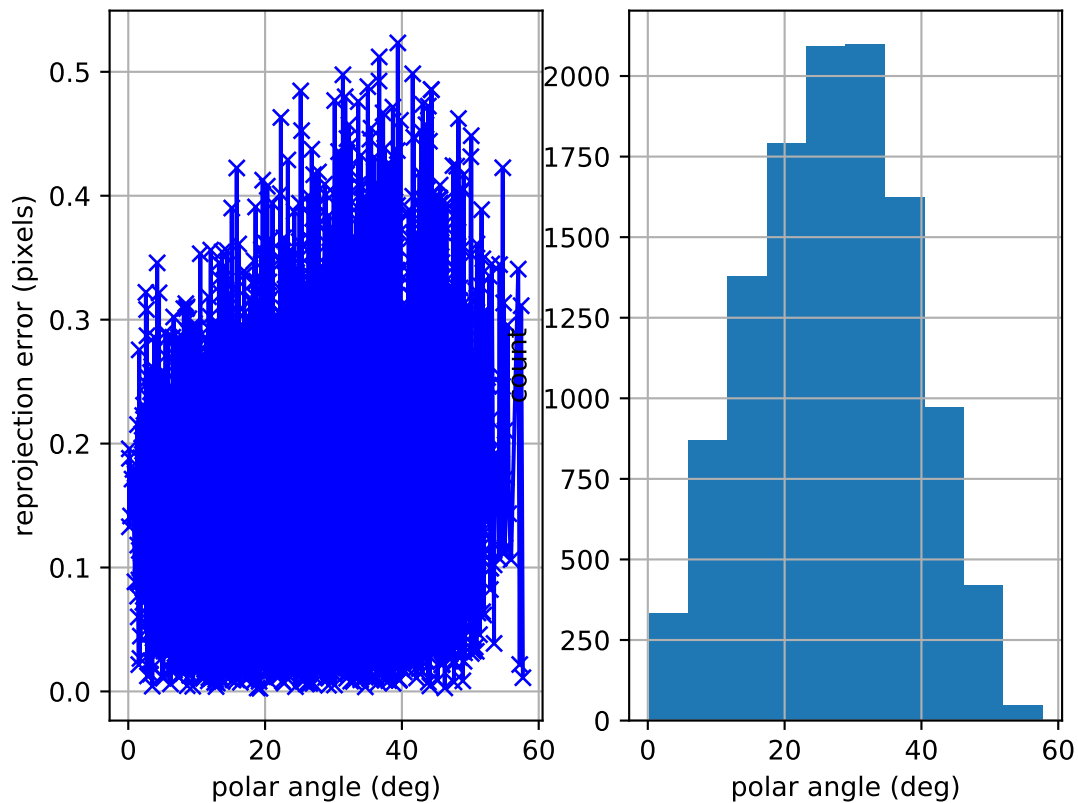
cam0: azimuthal error



cam0: reprojection errors

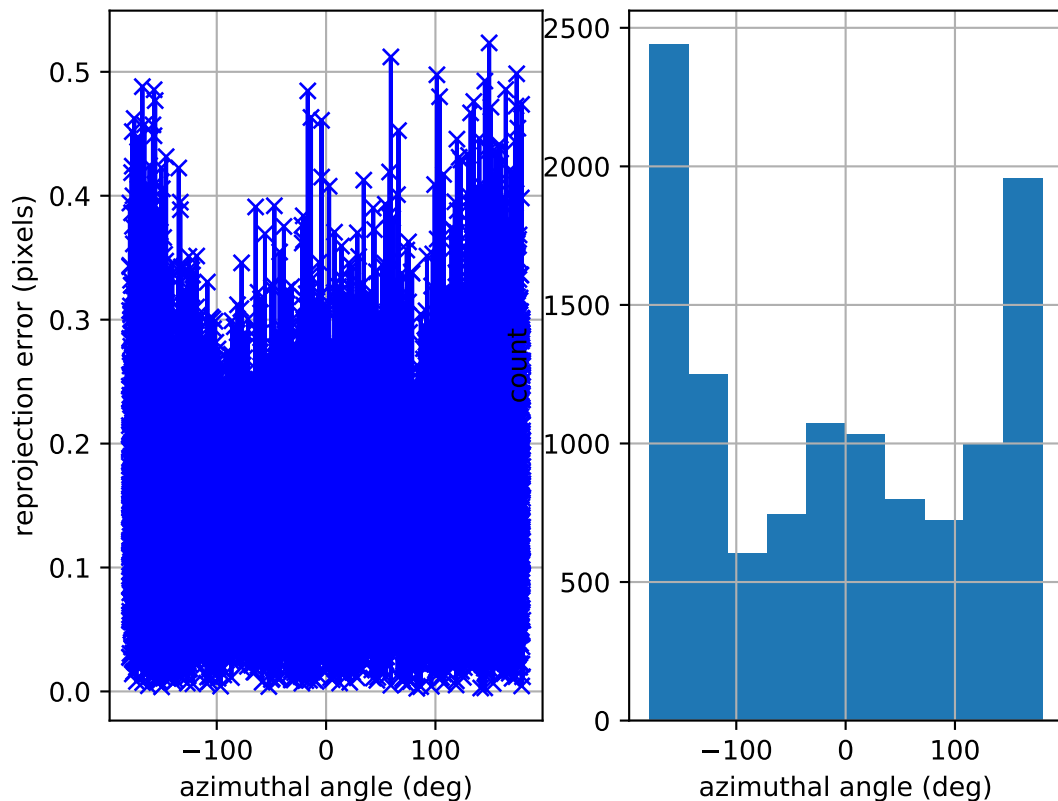


cam1: polar error

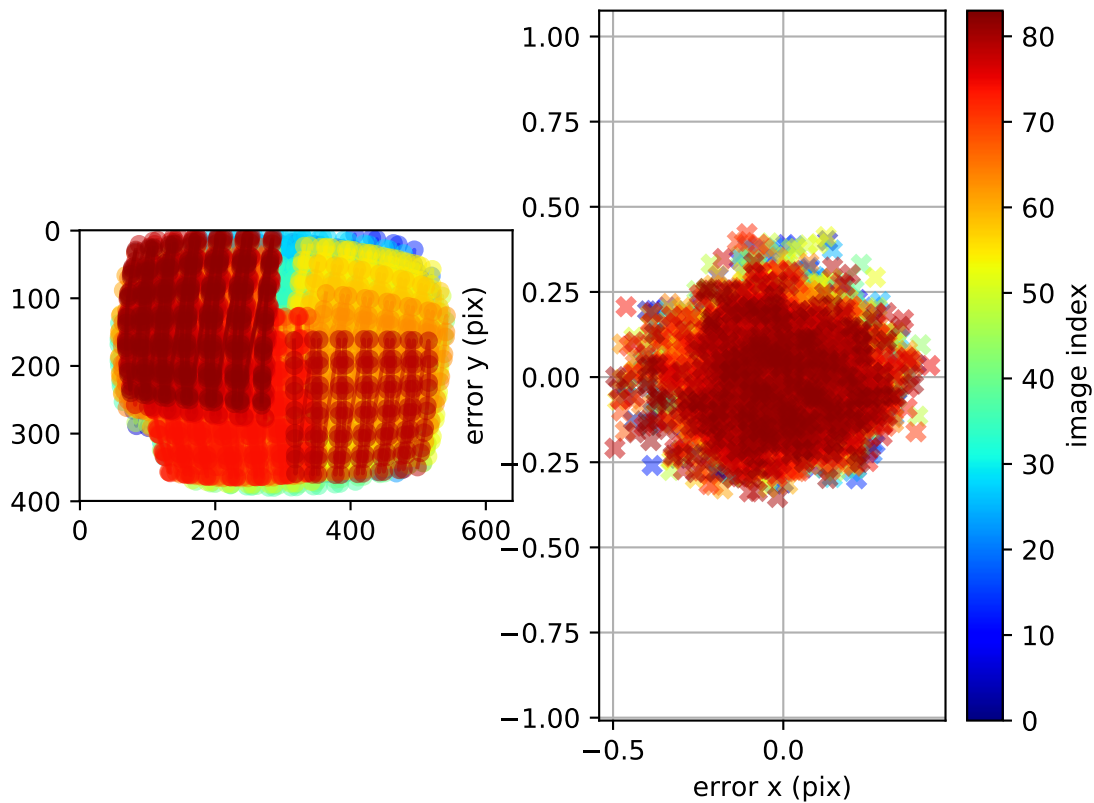




cam1: azimuthal error



cam1: reprojection errors



# Location of removed outlier corners

