

## Calibration results

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### Camera-system parameters:

cam0 (/cam0/image\_raw):

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

distortion: [] +- []

projection: [ 1.85592808 820.56242933 822.79900307 315.31252498 199.25758823] +- [ 0.00852861 3.84938141  
3.7440019 0.45994612 0.43596849]

reprojection error: [-0.000001, 0.000000] +- [0.116434, 0.103494]

cam1 (/cam1/image\_raw):

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

distortion: [] +- []

projection: [ 1.83534521 814.14416392 816.99707107 314.18233157 198.51868729] +- [ 0.00804579 3.29570233  
3.14117357 0.46857827 0.41470434]

reprojection error: [0.000001, -0.000000] +- [0.123263, 0.104846]

baseline T\_1 0:

q: [-0.00223556 -0.0077817 -0.01181796 0.99989739] +- [ 0.00078796 0.00171733 0.00018538]

t: [-0.08046275 -0.00009018 0.00102635] +- [ 0.00024239 0.0002376 0.00060982]

## Target configuration

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Type: aprilgrid

Tags:

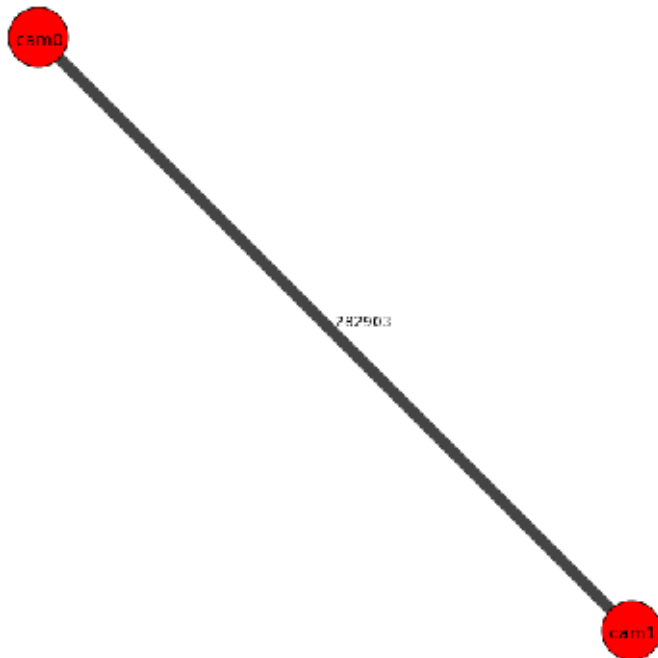
Rows: 6

Cols: 6

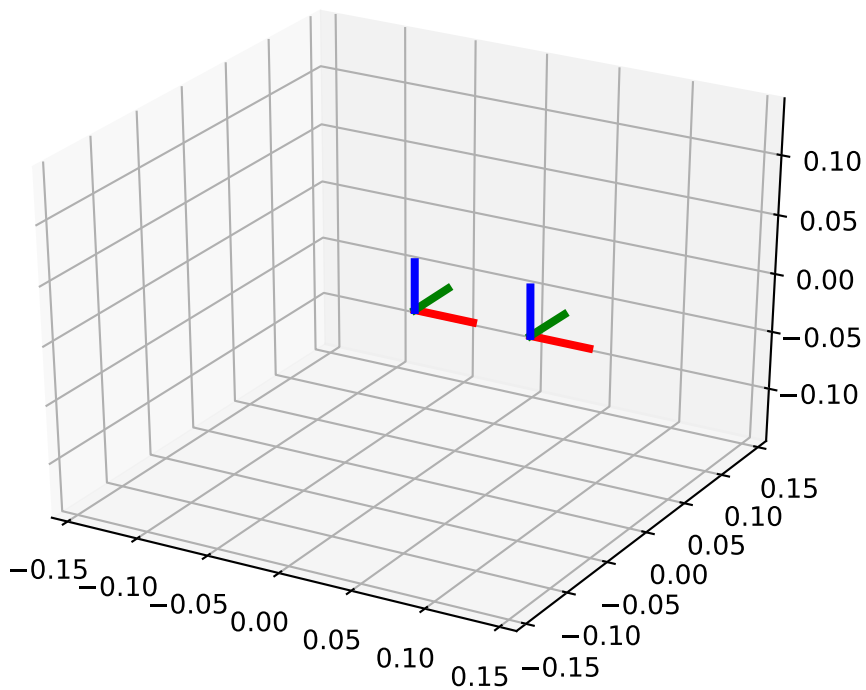
Size: 0.0312 [m]

Spacing 0.00959999976 [m]

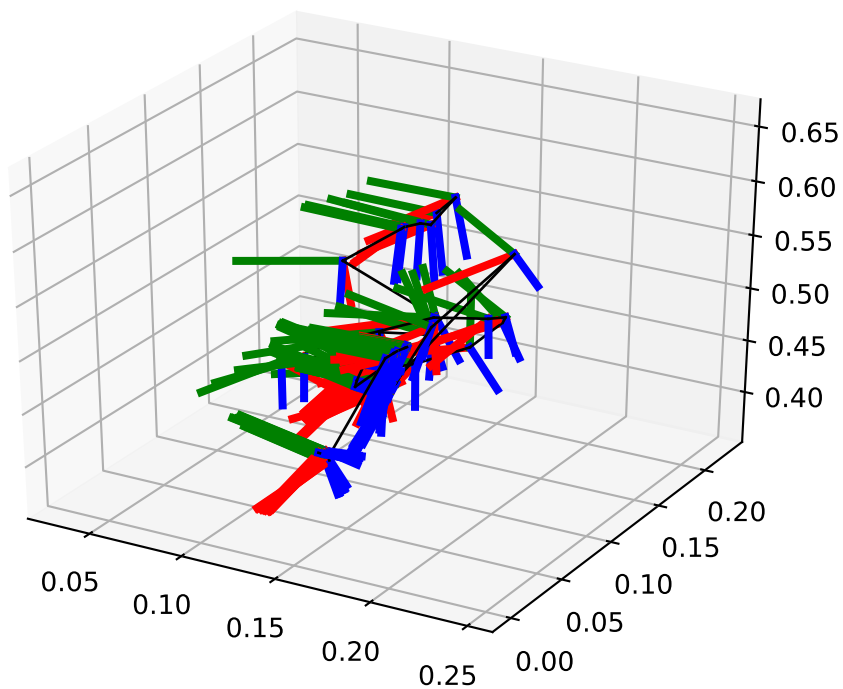
Inter-camera observations graph (edge weight=#mutual obs.)



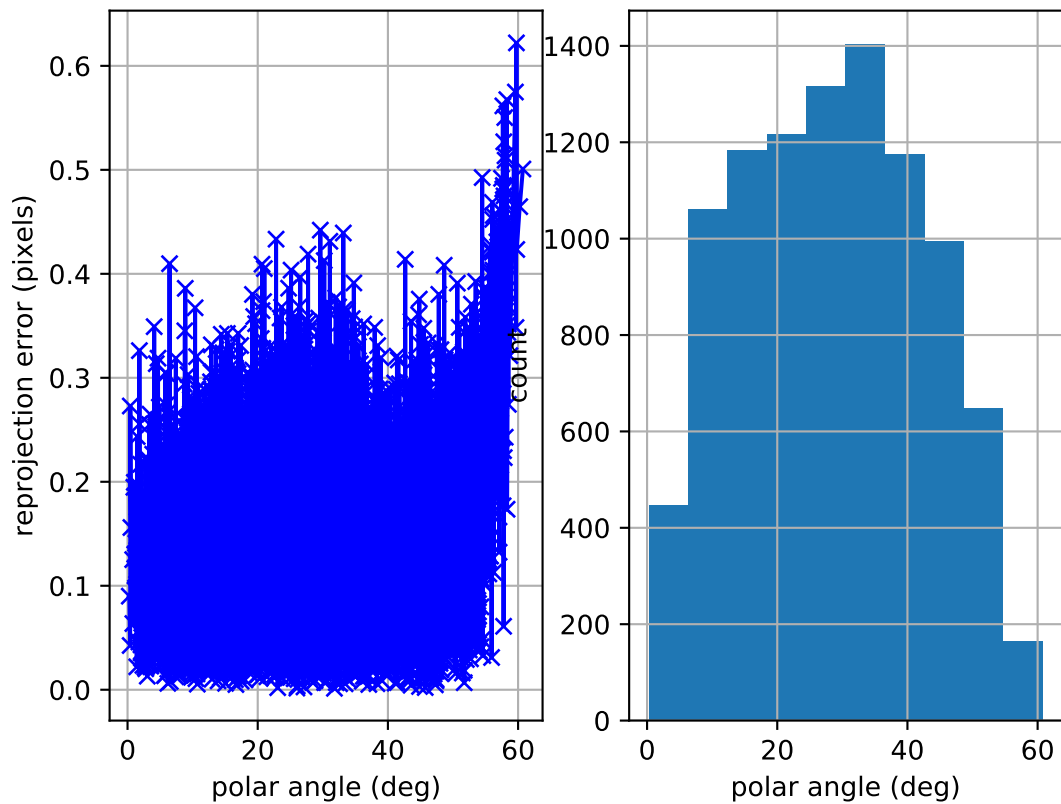
camera system



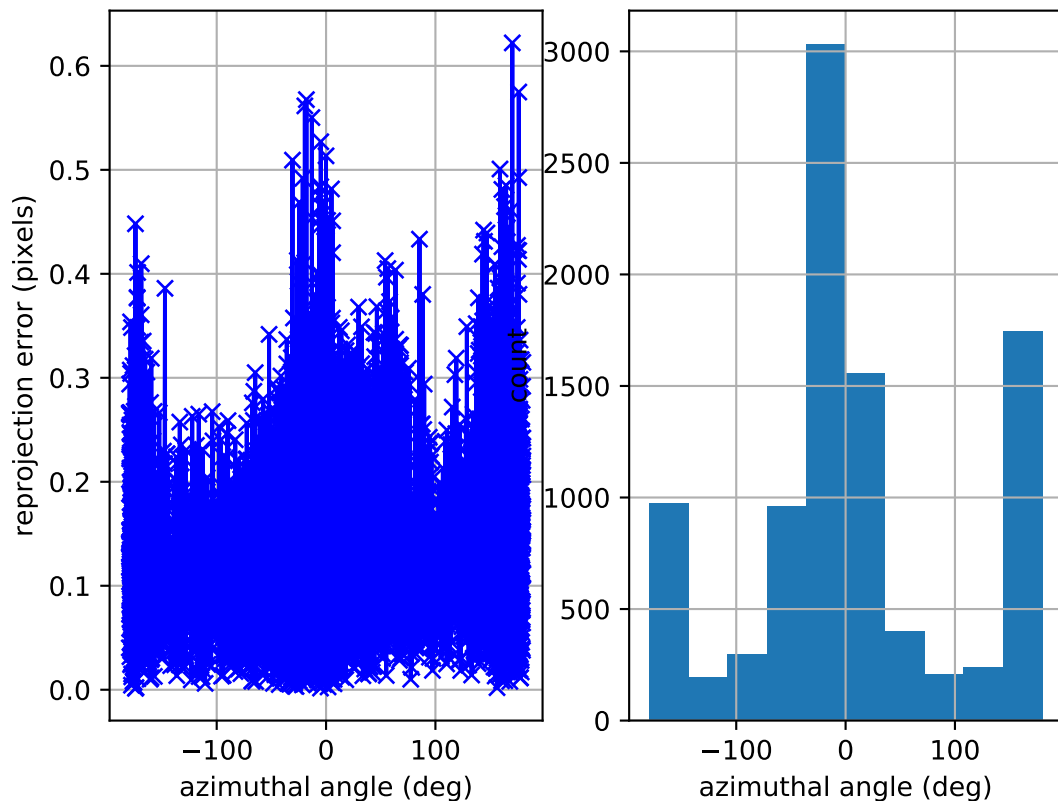
cam0: estimated poses



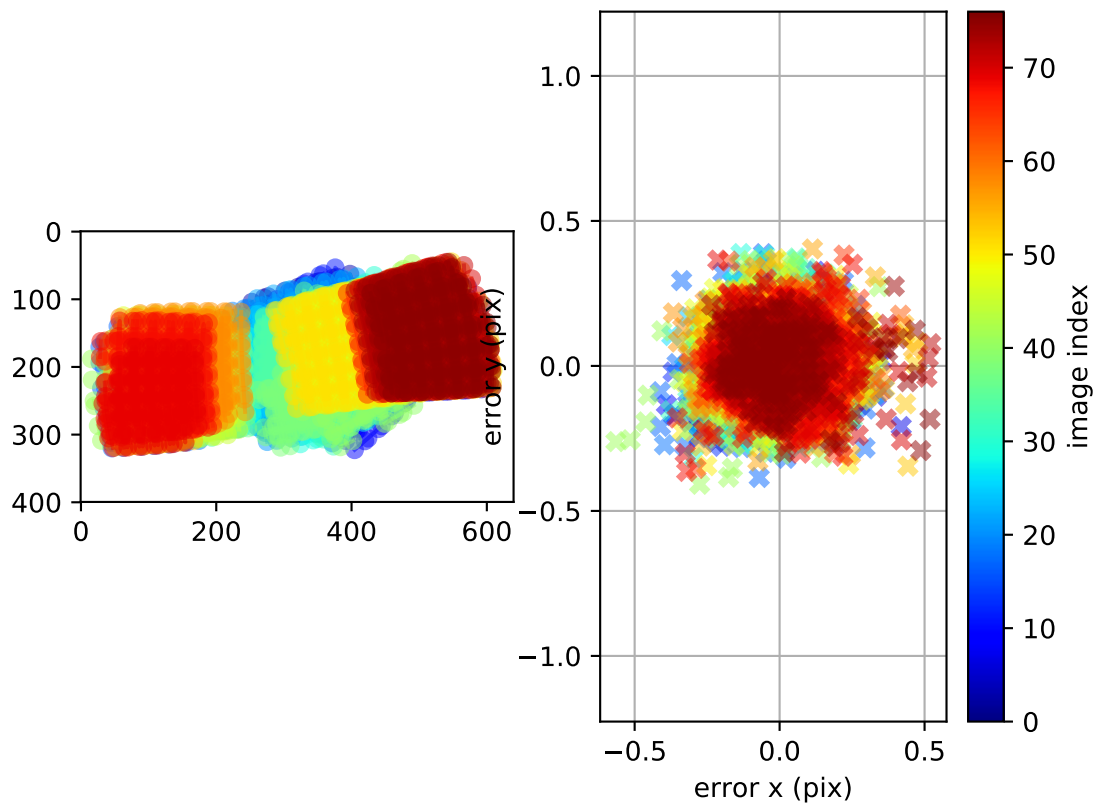
cam0: polar error



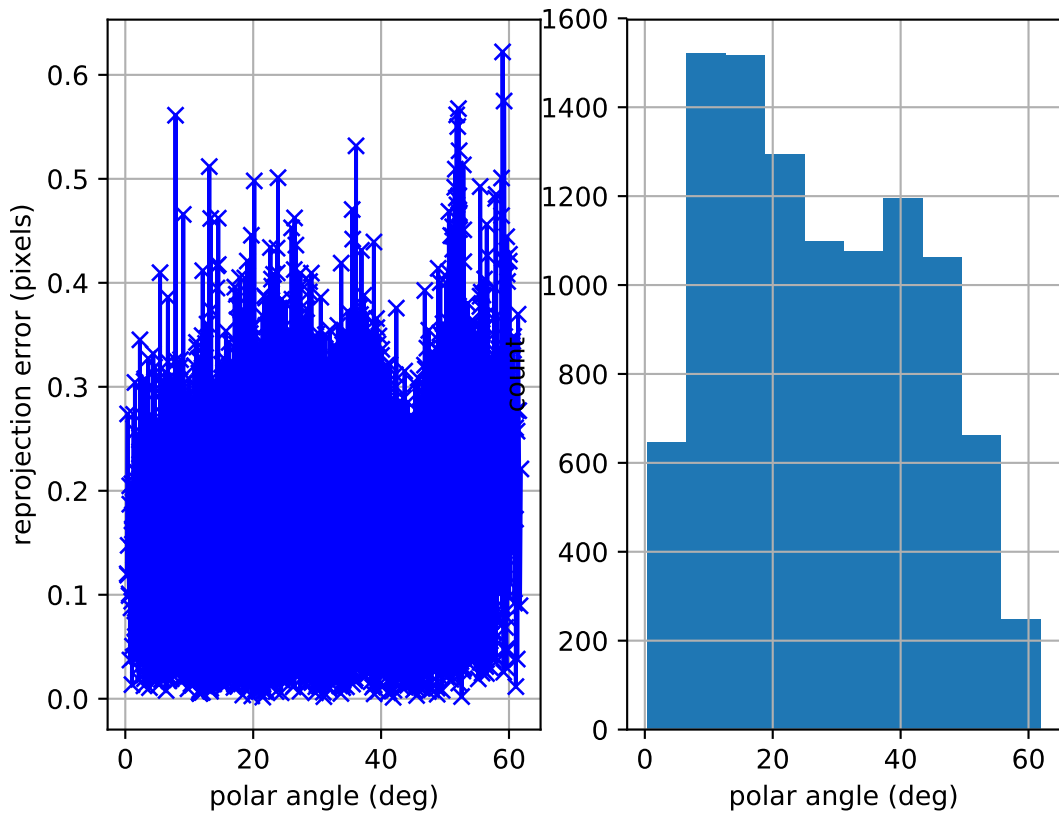
cam0: azimuthal error



cam0: reprojection errors

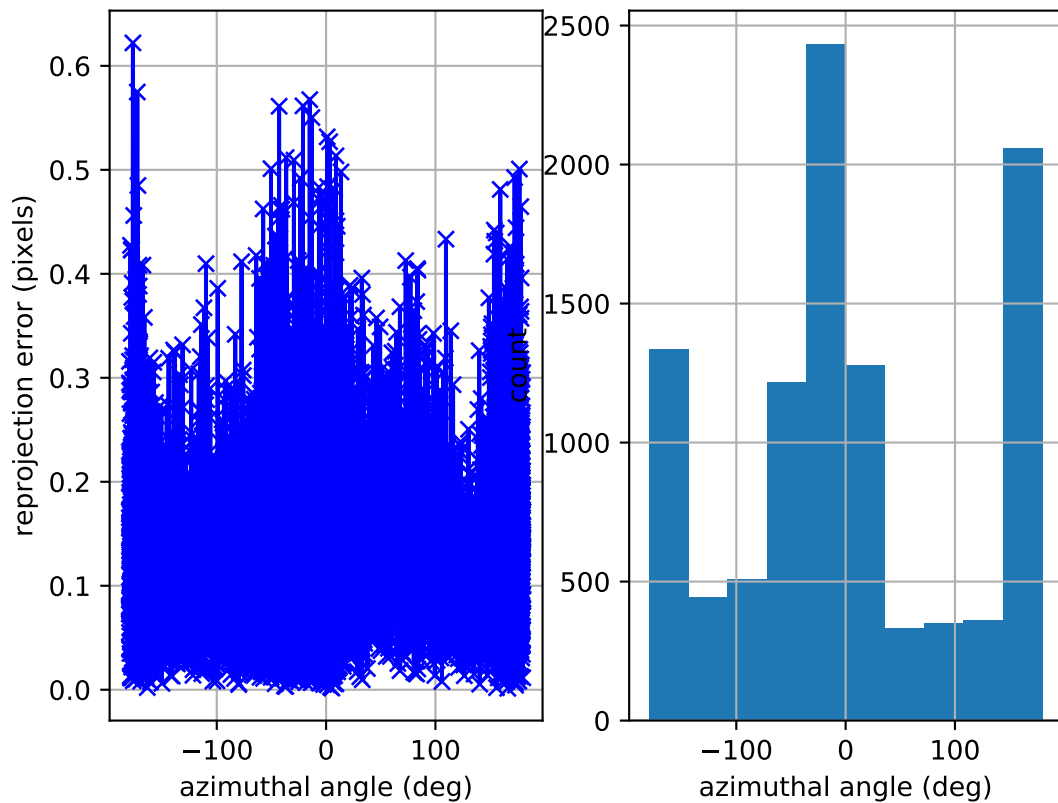


cam1: polar error

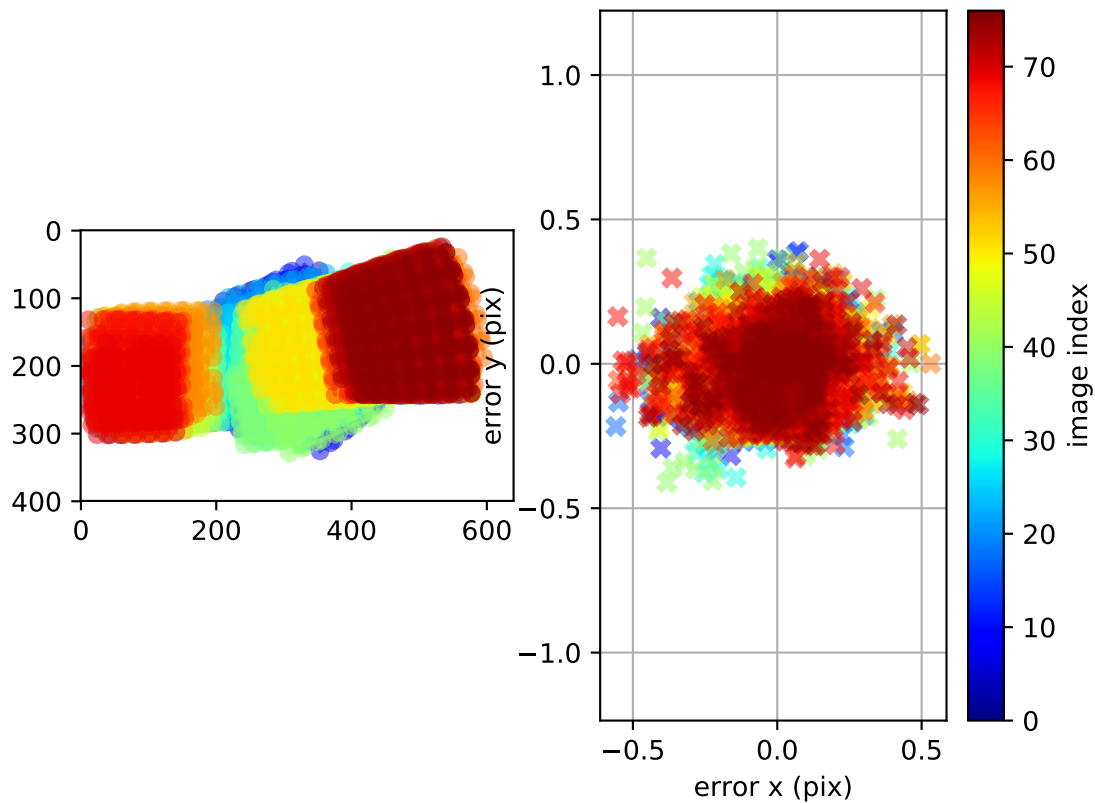




cam1: azimuthal error



cam1: reprojection errors



# Location of removed outlier corners

