Supplementary material Multicamera system calibration from visible and mirrored epipoles Paper ID: 2291

In this supplementary material we present the examples of the epipole and mirrored epipole calibration dataset images, as well as an additional synthetic test, excluded from the original paper for brevity.

A subset of calibration images from the dome multicamera system is shown in Fig.1. The same images together with the detected camera centers are presented in Fig.2.

Fig.3 shows a subset of calibration images from the VR-rig multicamera configuration. The same set of images together with the detected mirrored camera centers is presented in Fig.4.

An additional synthetic test, aimed at the evaluation of the accuracy of the recovered geometry under increasing number of cameras is presented in Fig.5. The virtual scene geometry and the error measure are similar to the ones described in the section 4.1 of the submitted paper. The noise variance has been set to 5px and the number of cameras has been increasing in the range [3; 30]. The test confirms the robustness of the proposed approach and shows an increase in the recovered geometry accuracy with increasing number of cameras.



Figure 1: Dome multicamera setup. Subset of calibration dataset images.



Figure 2: Dome multicamera setup. Subset of calibration dataset images with the detected camera centers.



Figure 3: VR rig multicamera setup. Subset of calibration dataset images.



Figure 4: VR rig multicamera setup. Subset of calibration dataset images with the detected mirrored camera centers.



Figure 5: Synthetic test. Rotation and translation errors vs. the number of cameras in the dome geometry.