## Self calibration method of binocular vision based on Conformal geometric algebra

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## Abstract

We will study binocular vision for 6-DOF robotic manipulator in conformal geometric algebra approach. We will focus on the case where some information as relative cameras positions, has been lost. In particular, we will use the construction of the manipulator to infer a self calibration method for cameras position based in binocular vision with incomplete information.

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AGACSE\_frolik\_stodola.pdf available at https://authorea.com/users/451661/articles/549869-self-calibration-method-of-binocular-vision-based-on-conformal-geometric-algebra