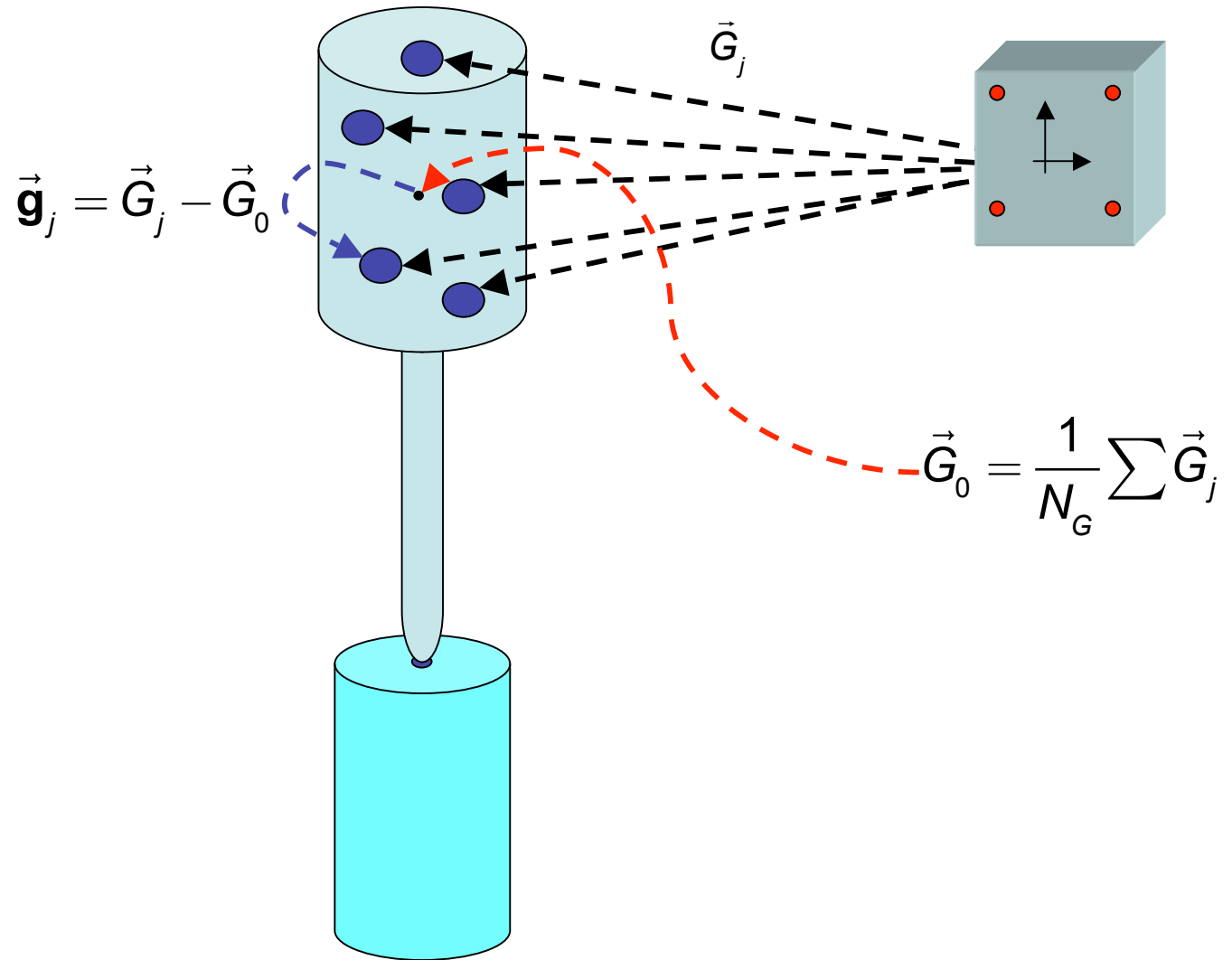
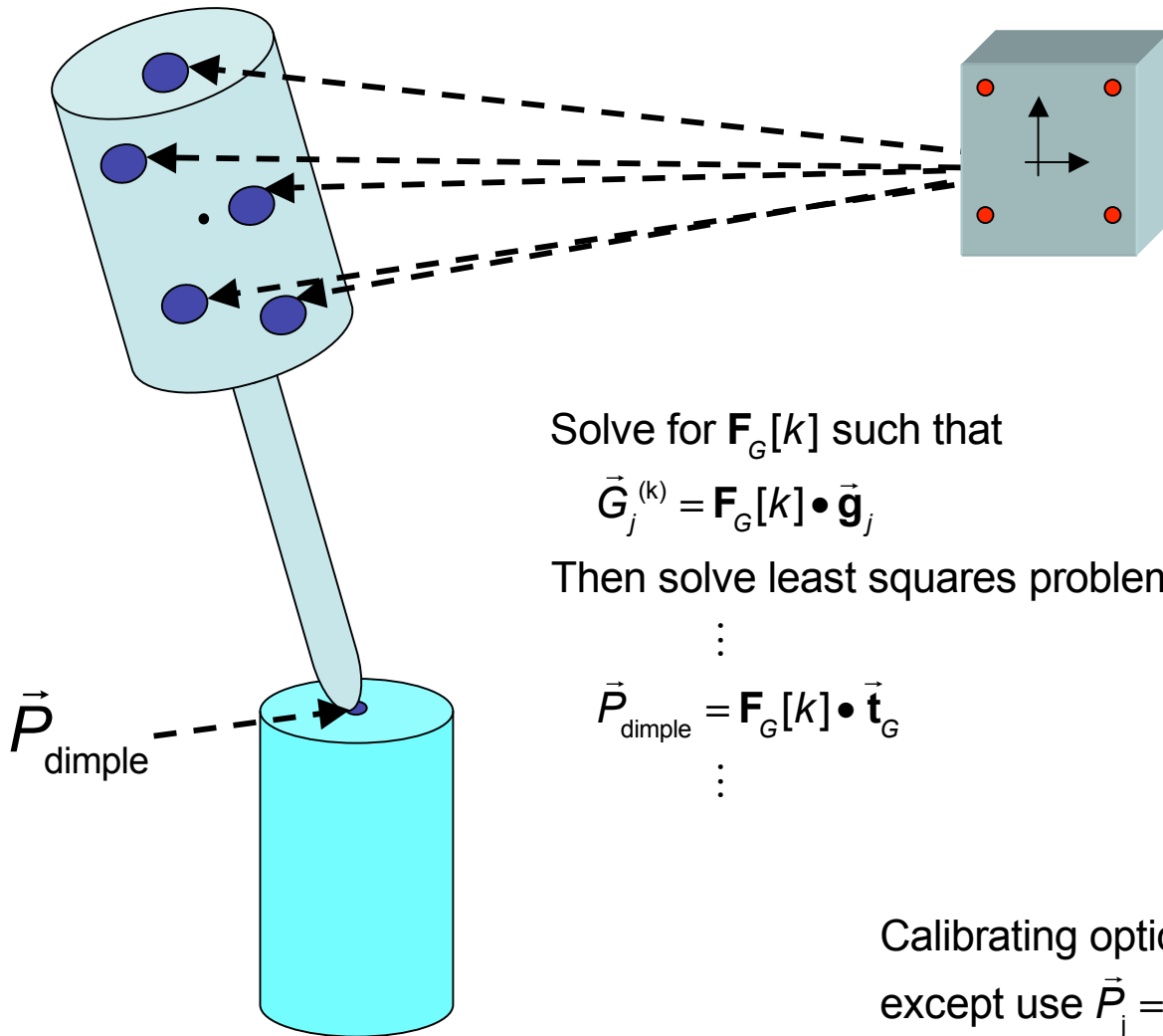


Defining the EM rigid body



Calibrating the EM Pointer (pivot calibration)



Solve for $\mathbf{F}_G[k]$ such that

$$\vec{G}_j^{(k)} = \mathbf{F}_G[k] \cdot \vec{g}_j$$

Then solve least squares problem

⋮

$$\vec{P}_{\text{dimple}} = \mathbf{F}_G[k] \cdot \vec{t}_G$$

⋮

Calibrating optical pointer is similar except use $\vec{P}_j = \mathbf{F}_D \cdot \vec{H}_j$ instead of \vec{G}_j

