

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.04724997 0.07903139 0.00047211 -0.00107263] +- [0.00107032 0.00228782 0.00008202 0.00005861]
projection: [1031.35604339 1031.46938163 634.87623341 366.06997172] +- [0.14972523 0.15325945 0.00449393
0.12777454]

reprojection error: [0.000172, 0.000027] +- [0.525161, 0.451238]

cam1 (/prophesee/right/events):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.05098765 0.07404911 0.00174134 0.00001399] +- [0.00110065 0.00231323 0.00007914 0.00005716]
projection: [1031.1878257 1031.23246009 636.42060033 368.8004534] +- [0.15183343 0.15648462 0.00748966
0.08072262]

reprojection error: [0.000075, -0.000006] +- [0.698012, 0.576714]

cam2 (/ovc/left/image_mono/compressed):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.39387206 0.15810057 -0.00006533 0.0005881] +- [0.00056506 0.00096626 0.00005581 0.0000368]
projection: [1056.57866761 1057.12818717 675.67492554 336.19383134] +- [0.12653779 0.13163296 0.02032057
0.20254831]

reprojection error: [0.000020, -0.000087] +- [0.194089, 0.152722]

cam3 (/ovc/right/image_mono/compressed):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.39298909 0.1531909 -0.00005106 0.00086113] +- [0.00048803 0.0007491 0.00005178 0.00003544]
projection: [1051.68258625 1052.23214647 675.81968435 328.28496795] +- [0.11821579 0.12732458 0.01581542
0.20025359]

reprojection error: [-0.000048, -0.000143] +- [0.205874, 0.151870]

cam4 (/ovc/rgb/image_color/compressed):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.41425487 0.1842289 0.00005025 0.00015636] +- [0.00077341 0.00176619 0.00005538 0.00003923]
projection: [1262.36624986 1262.51069008 651.80988776 367.81628728] +- [0.13365259 0.13820968 0.00741837
0.08292679]

reprojection error: [-0.000045, -0.000081] +- [0.237578, 0.242749]

baseline T_1_0:

q: [-0.00147683 0.00212623 -0.0003062 0.9999966] +- [0.0001231 0.00006626 0.00003938]

t: [-0.12031256 0.00089407 -0.00001665] +- [0.00004351 0.00003435 0.00012337]

baseline T_2_1:

q: [0.0002568 -0.00204509 -0.00519191 0.9999844] +- [0.00024137 0.00006717 0.00003712]

t: [0.12020068 0.06918211 0.00390225] +- [0.0000402 0.00003146 0.00011475]

baseline T_3_2:

q: [0.00054983 -0.00157645 0.00018907 0.99999859] +- [0.00029555 0.00005847 0.00003129]

t: [-0.1199956 -0.00014169 0.00055935] +- [0.00003171 0.00002504 0.00009679]

baseline T_4_3:

q: [0.00158933 0.00328086 0.0004553 0.99999325] +- [0.00024283 0.00005334 0.00003111]

t: [0.08888866 0.00619016 0.0031727] +- [0.00003132 0.00002424 0.00008896]

Target configuration

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Type: aprilgrid

Tags:

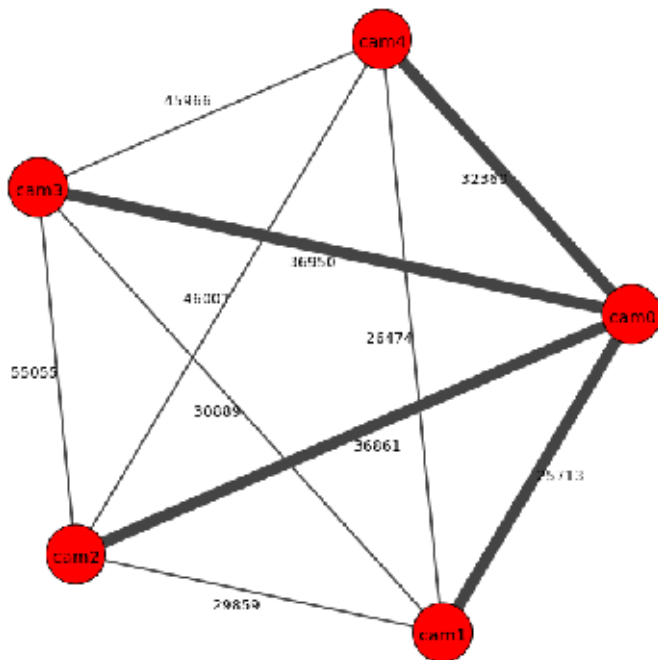
Rows: 5

Cols: 7

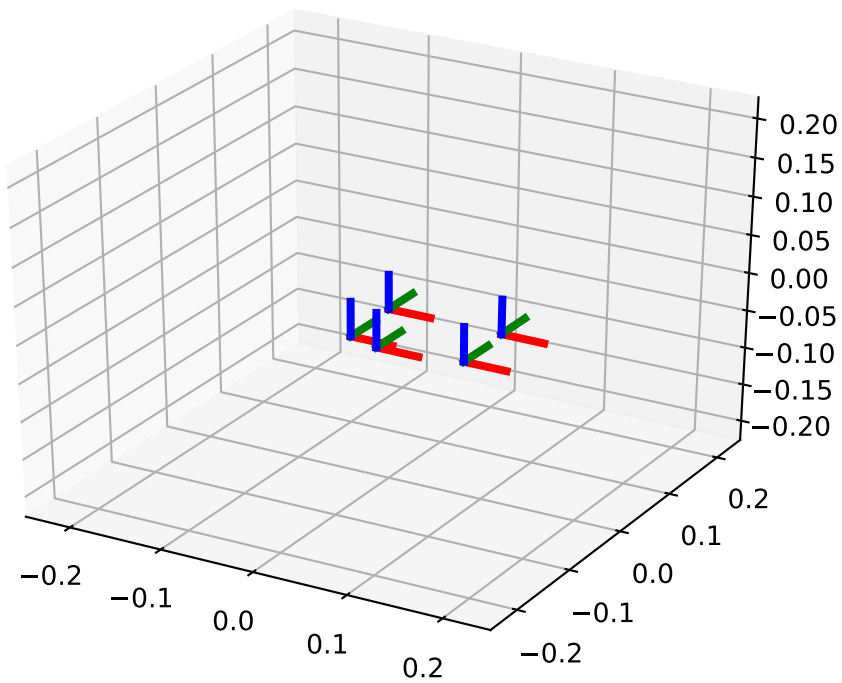
Size: 0.04 [m]

Spacing 0.01 [m]

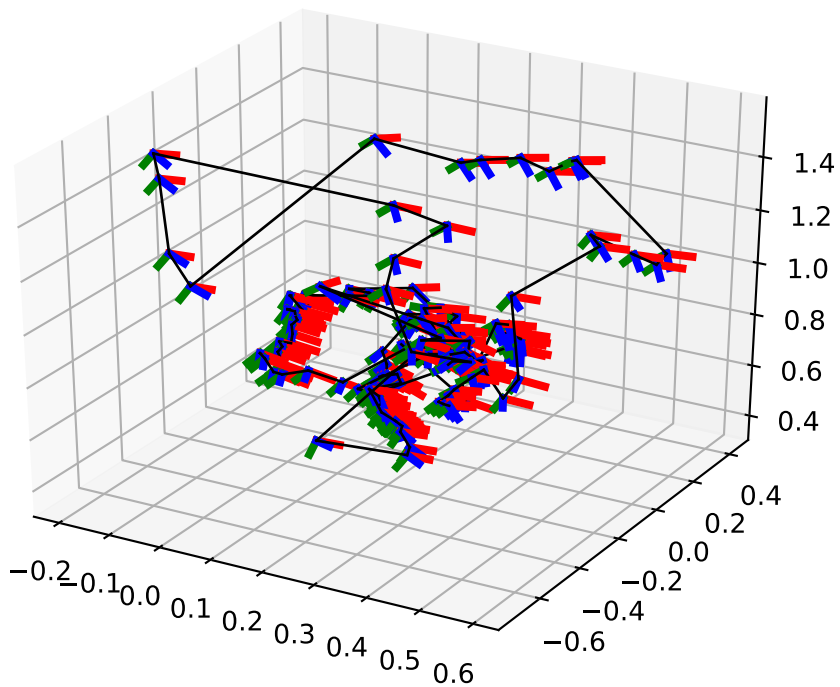
Inter-camera observations graph (edge weight=#mutual obs.)



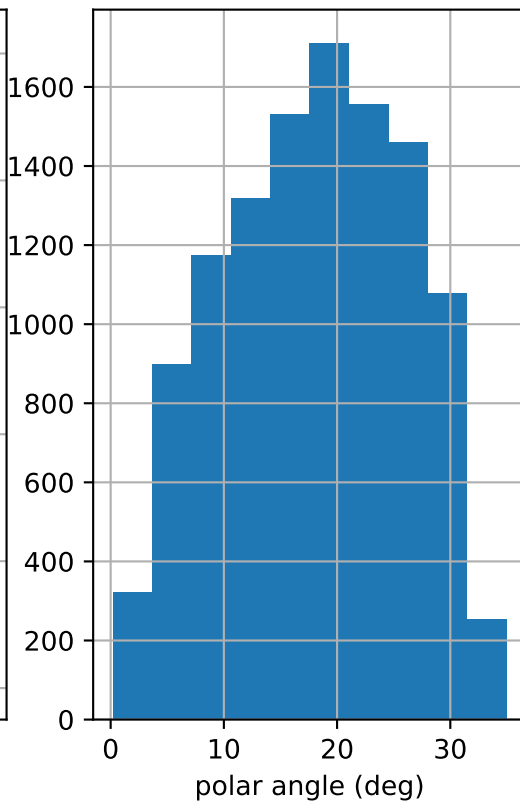
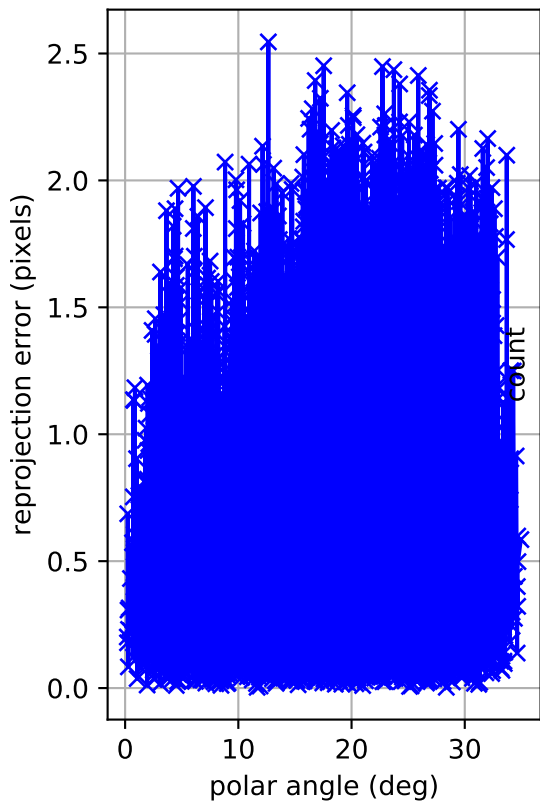
camera system



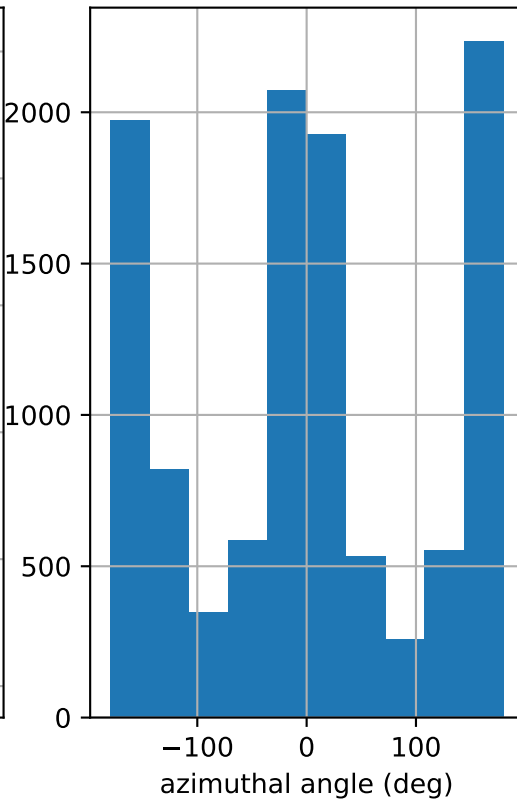
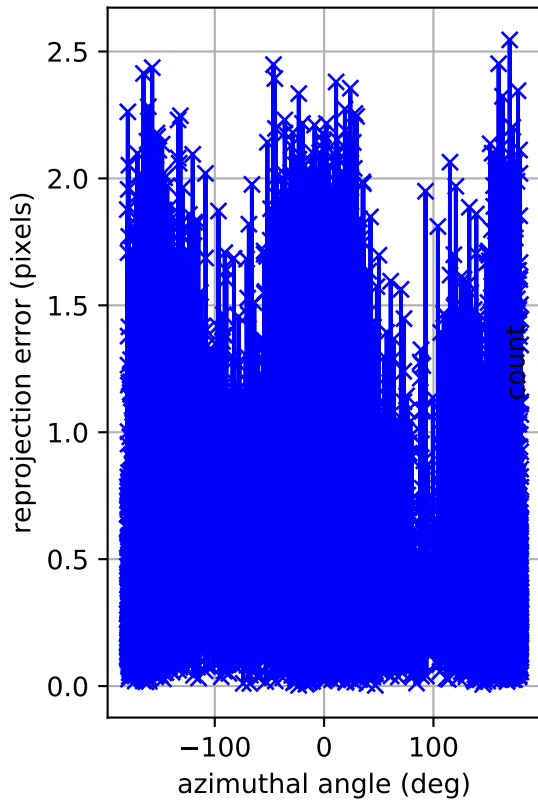
cam0: estimated poses



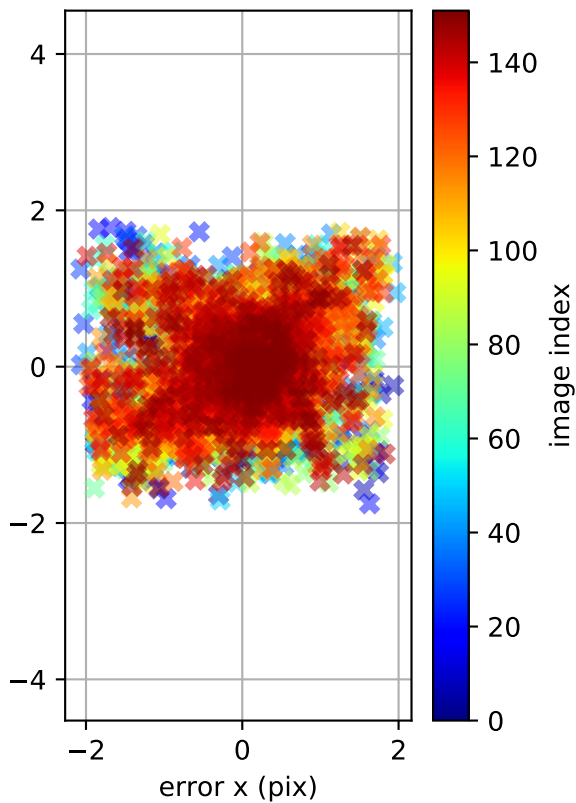
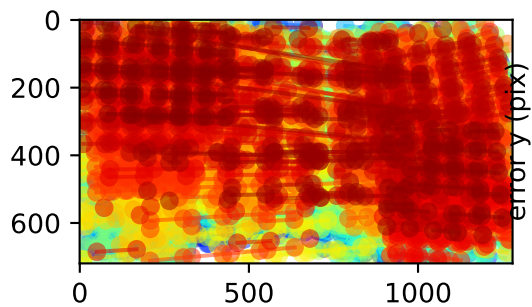
cam0: polar error



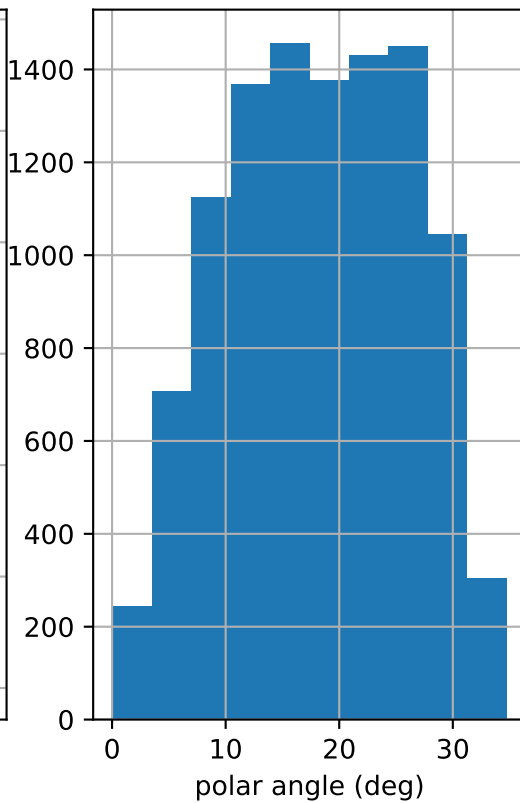
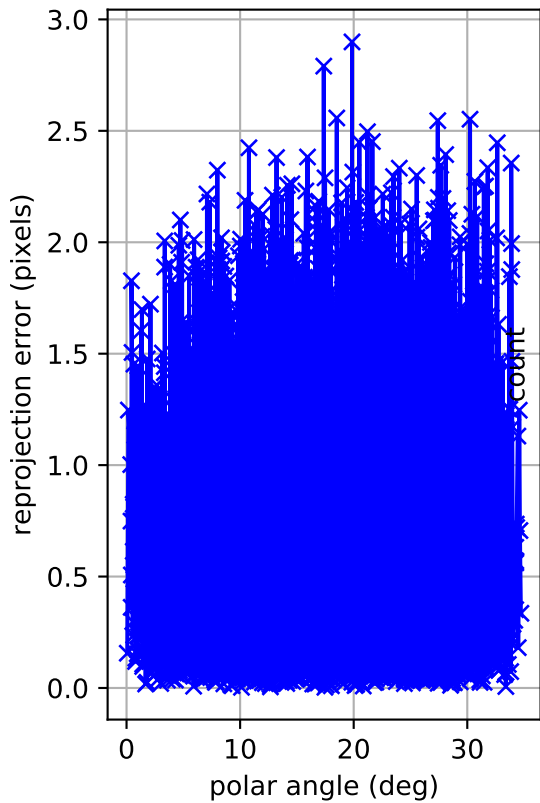
cam0: azimuthal error



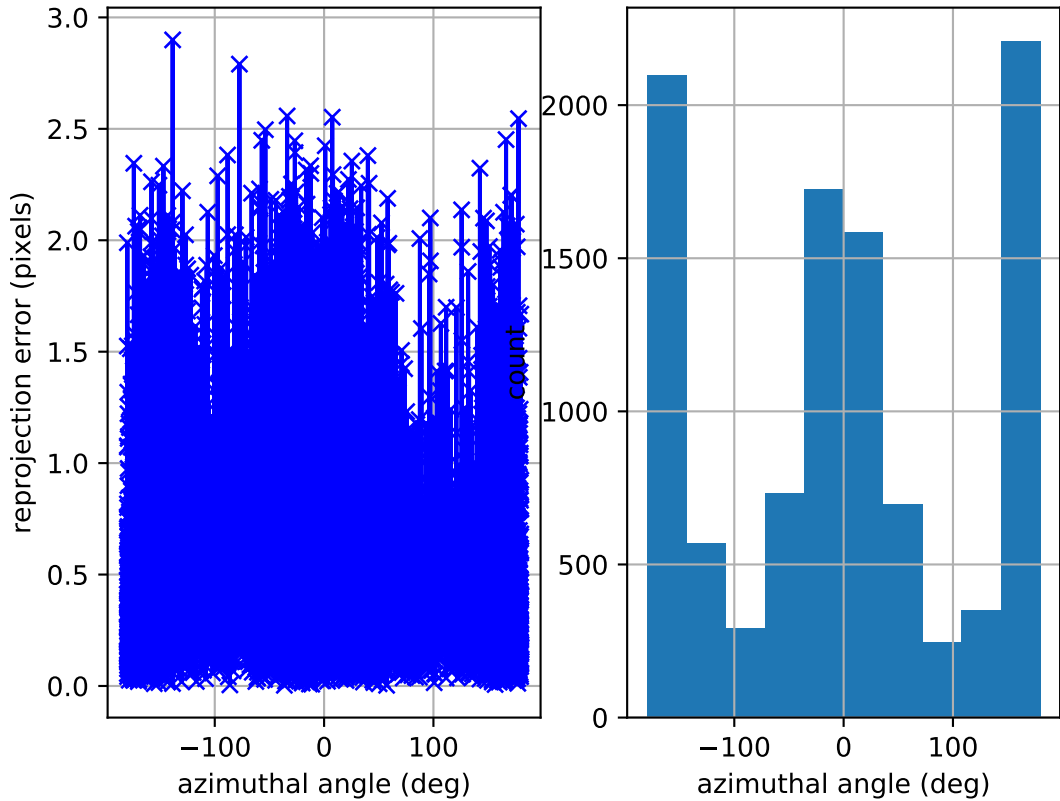
cam0: reprojection errors



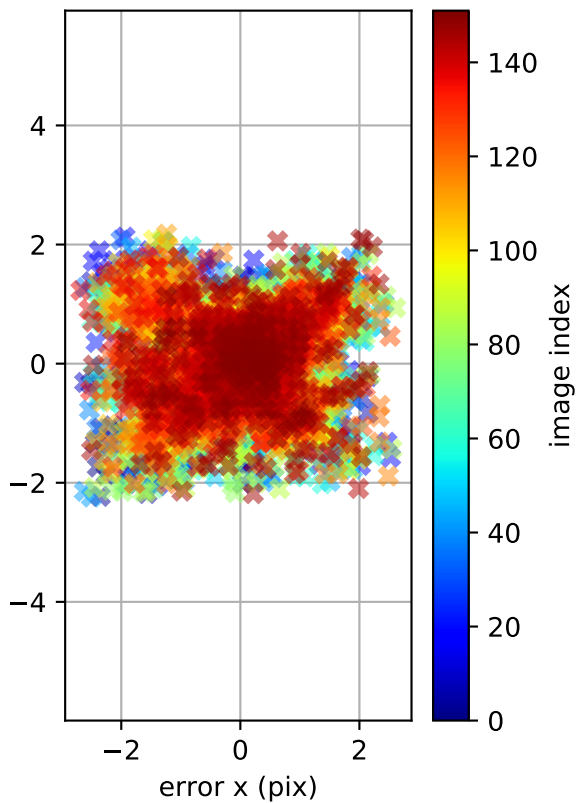
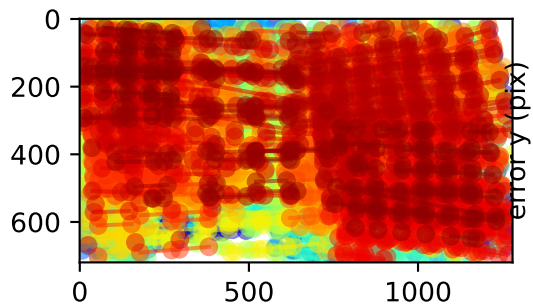
cam1: polar error



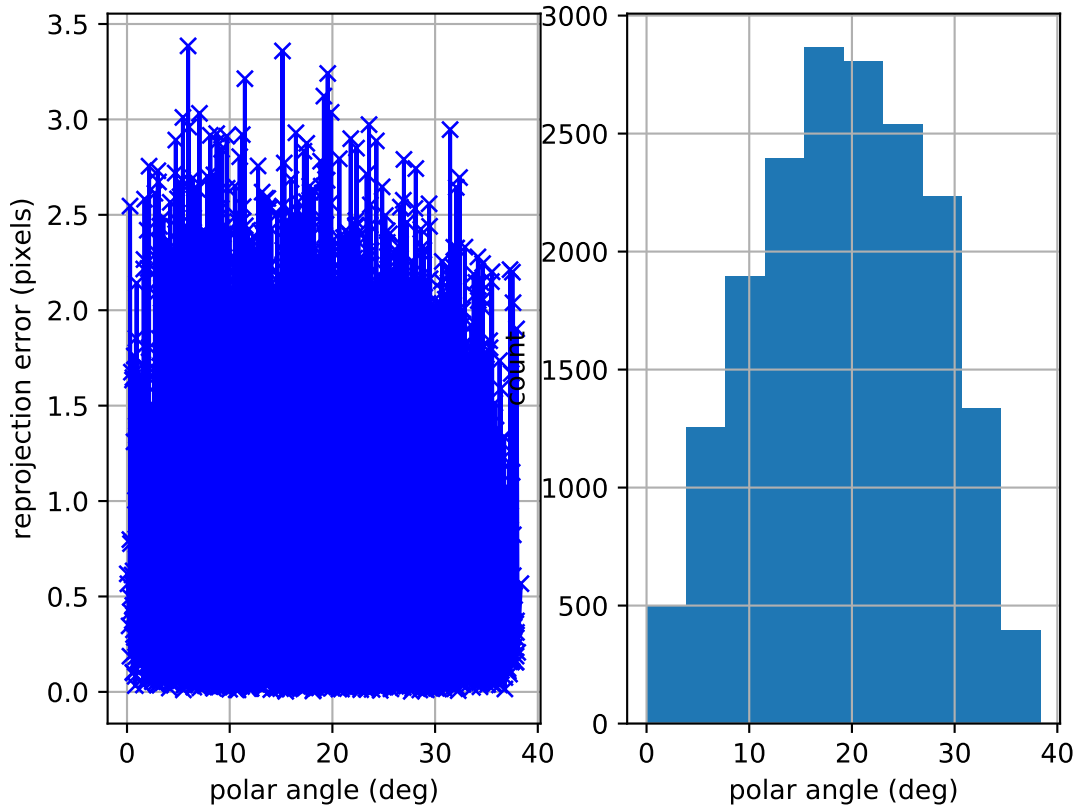
cam1: azimuthal error



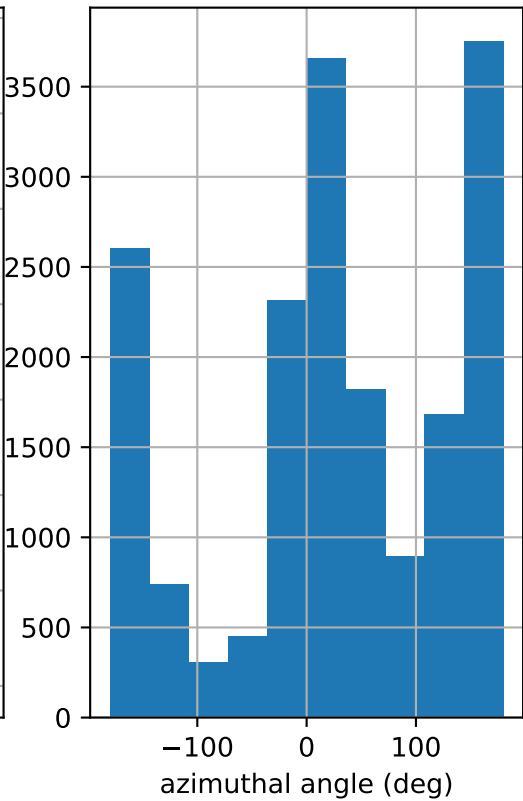
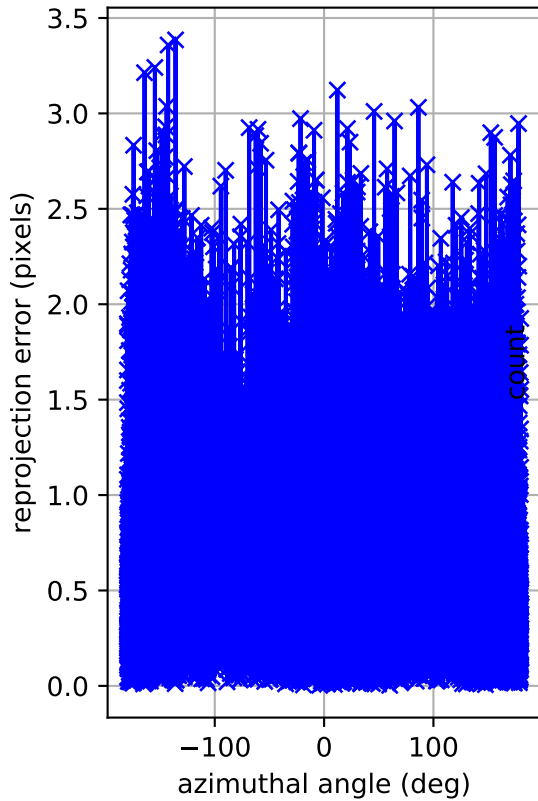
cam1: reprojection errors



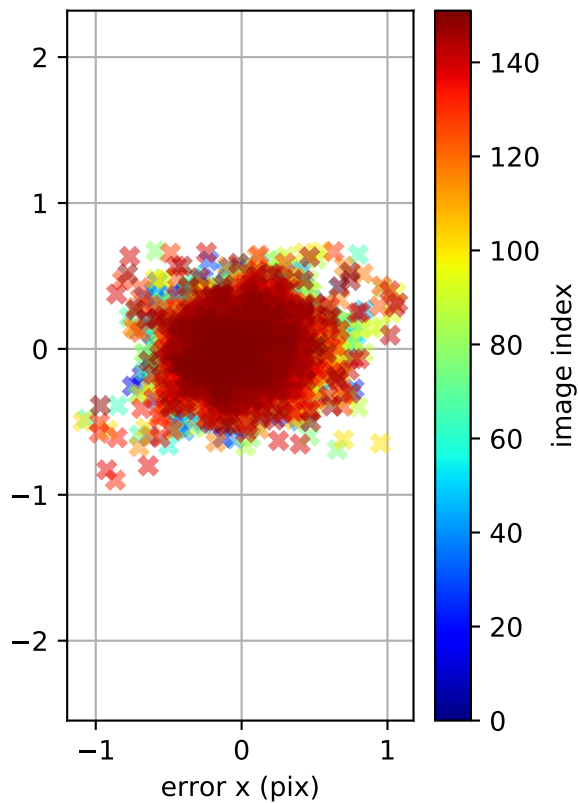
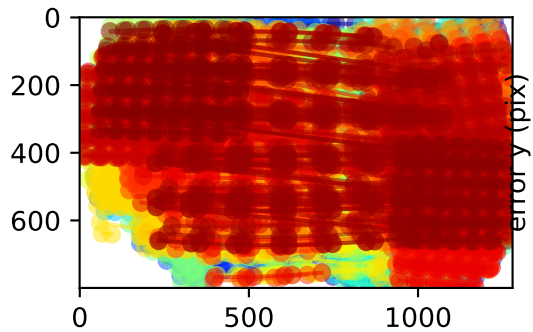
cam2: polar error



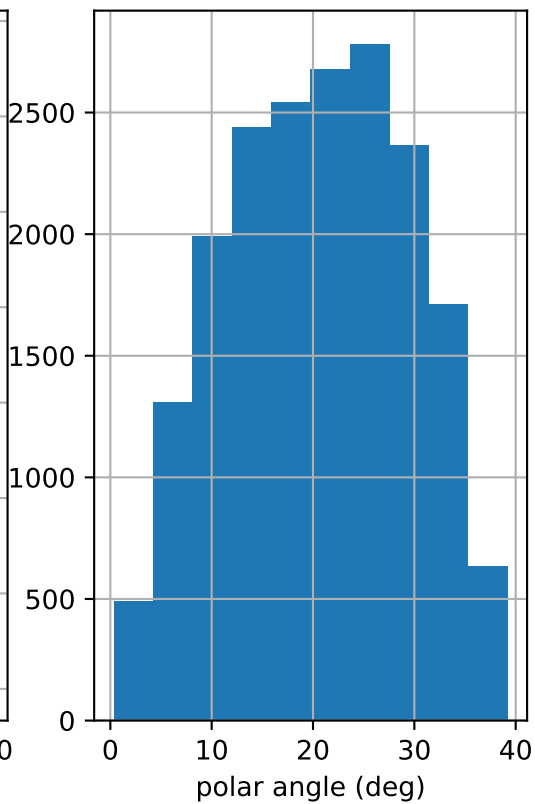
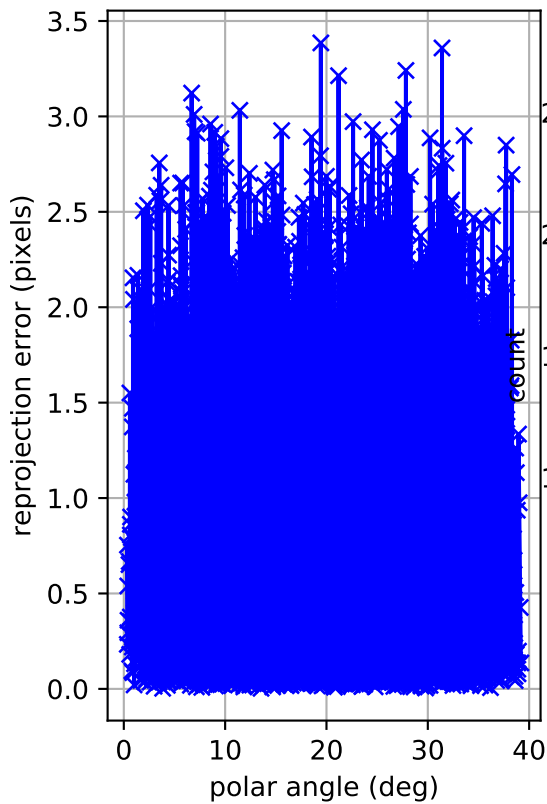
cam2: azimuthal error



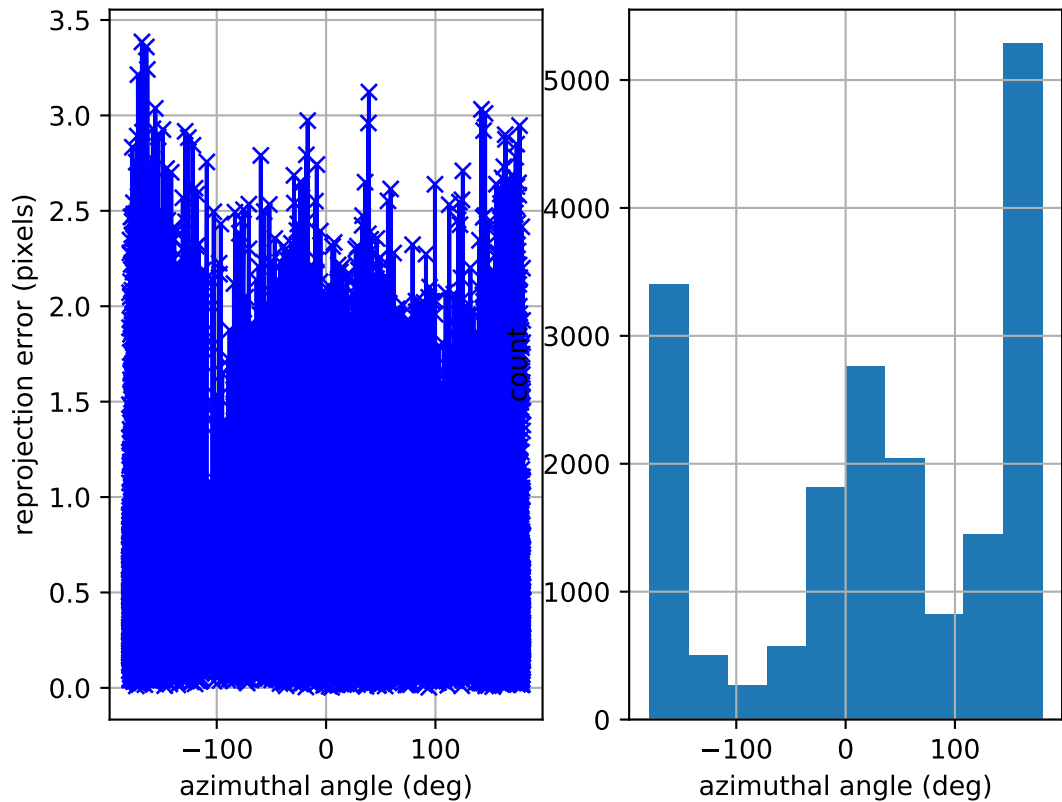
cam2: reprojection errors



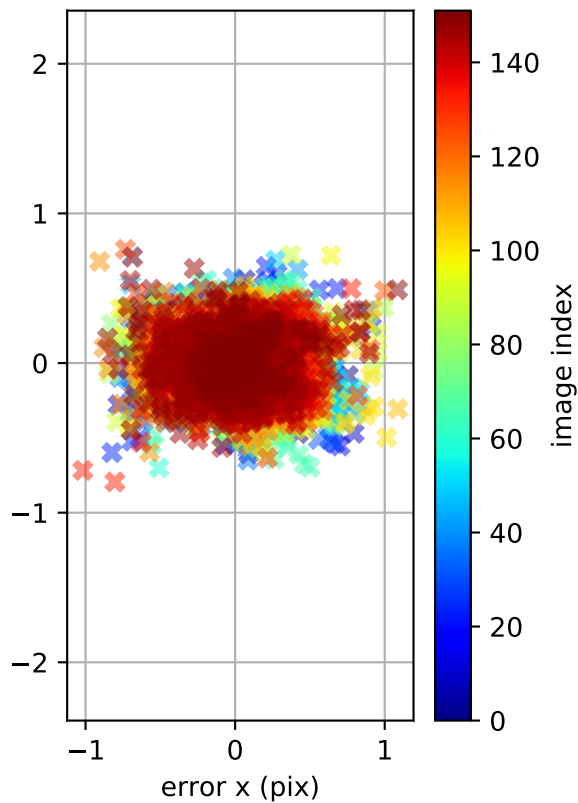
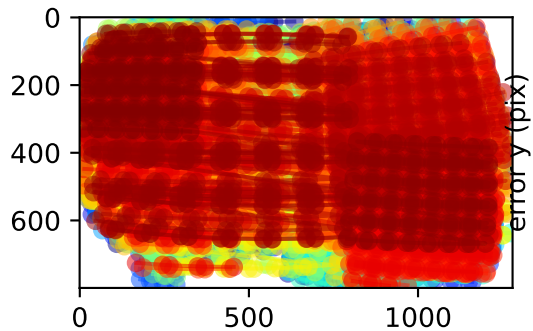
cam3: polar error



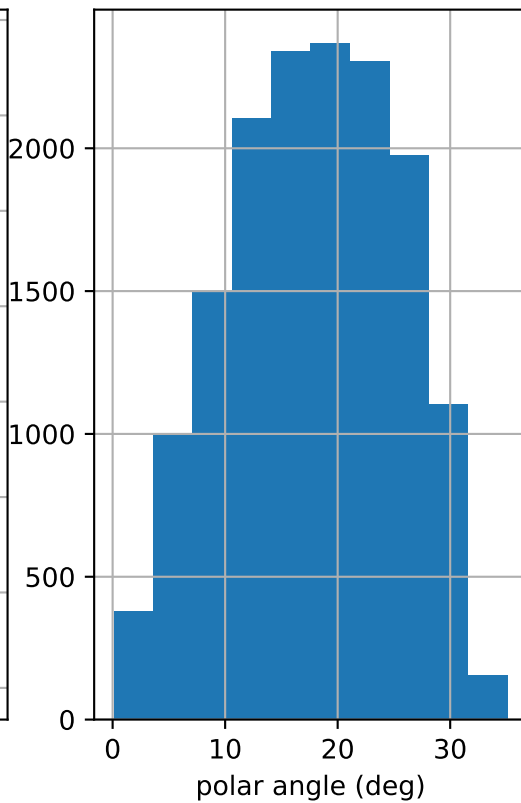
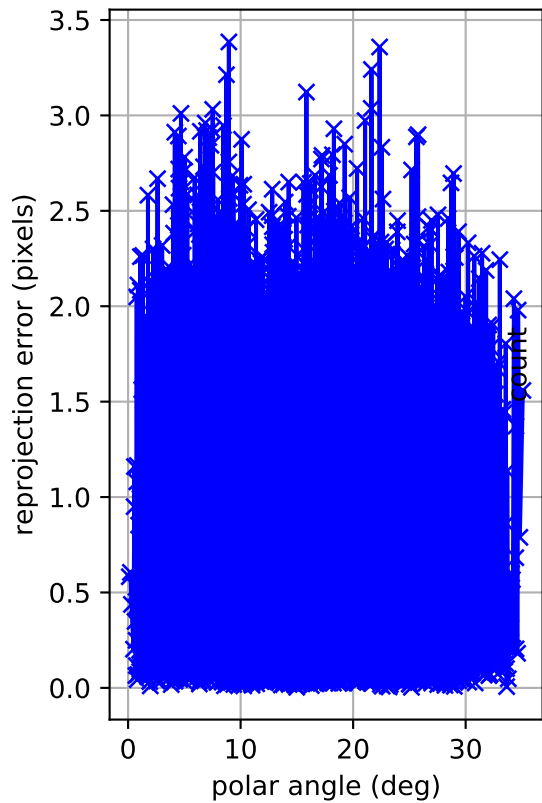
cam3: azimuthal error



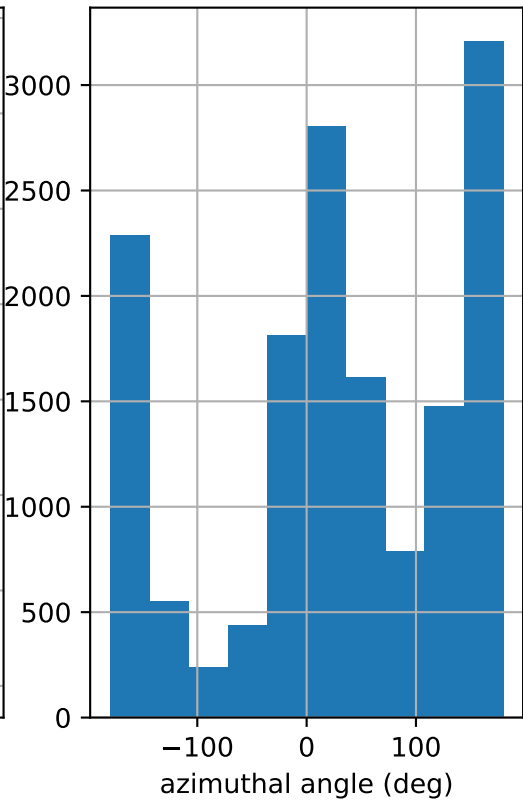
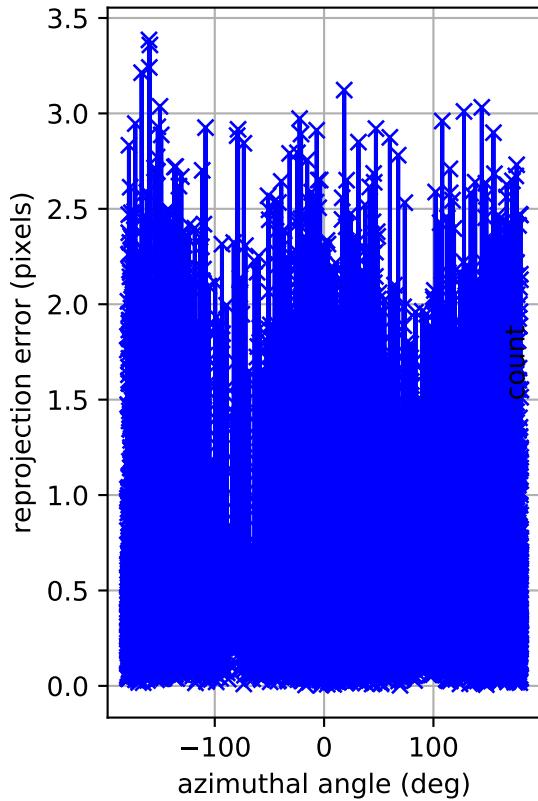
cam3: reprojection errors



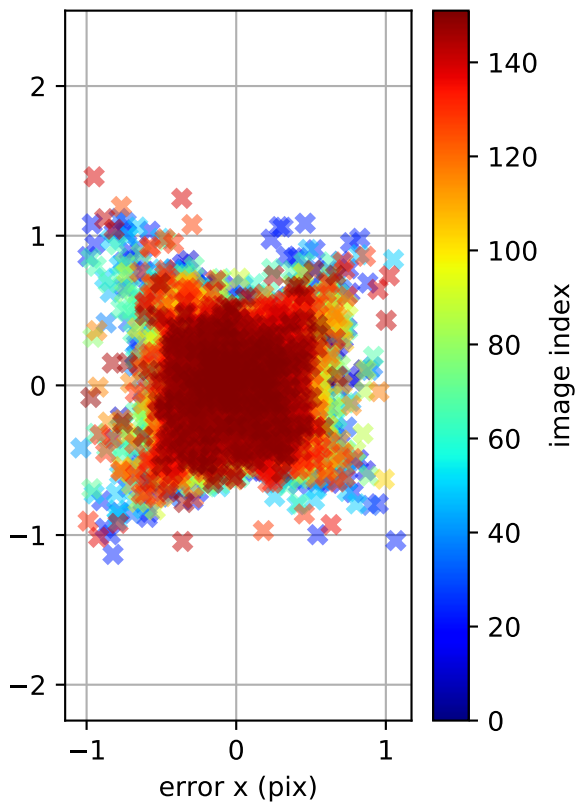
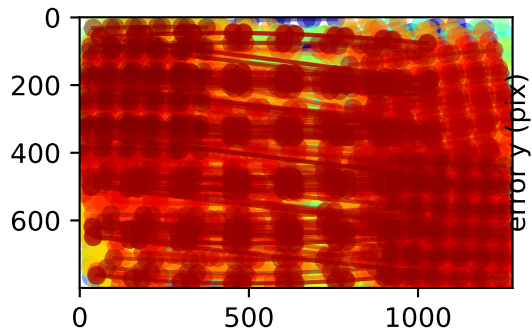
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

