

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04534182 0.07904291 0.00058656 -0.00160291] +- [0.00101256 0.00215731 0.00008001 0.00005818]
projection: [1031.66911192 1031.56266836 633.61893905 366.39724655] +- [0.13634161 0.12977286 0.02396052 0.15396812]

reprojection error: [0.000159, -0.000009] +- [0.532983, 0.4731119]

cam1 (/prophesee/right/events):

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

distortion: [-0.05192828 0.08277191 0.00157818 -0.00011523] +- [0.00106508 0.00233975 0.00007536 0.00005713]
projection: [1031.54235269 1031.83110074 635.25505327 367.77306988] +- [0.1396449 0.13412298 0.00303511 0.03574807]

reprojection error: [0.000152, -0.000039] +- [0.637371, 0.588925]

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

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

distortion: [-0.39112513 0.15366489 -0.00016209 0.00069006] +- [0.00049373 0.00079306 0.00004874 0.00003436]
projection: [1056.91855957 1057.12307323 672.65708896 336.29383035] +- [0.11371893 0.11191738 0.00809198 0.17655184]

reprojection error: [0.000156, -0.000163] +- [0.193444, 0.173362]

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

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

distortion: [-0.3908145 0.14956593 -0.00033534 0.00123796] +- [0.00043885 0.0006411 0.00005083 0.00003454]
projection: [1052.23774566 1052.97614352 669.99421422 329.34744122] +- [0.11295227 0.11352547 0.01519551 0.18551648]

reprojection error: [0.000228, -0.000285] +- [0.217207, 0.180909]

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

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

distortion: [-0.41246966 0.18020904 -0.00004239 0.0002896] +- [0.00073184 0.00164147 0.00005435 0.00003924]
projection: [1263.42027974 1263.37380405 647.93791266 367.41945294] +- [0.13119325 0.1247074 0.00491235 0.04648485]

reprojection error: [0.000135, 0.000027] +- [0.257108, 0.267413]

baseline T_1_0:

q: [-0.00083484 0.00231473 -0.00033041 0.99999692] +- [0.00013556 0.00005901 0.00003766]

t: [-0.12017314 0.00093483 0.00024772] +- [0.00003648 0.00003386 0.00011014]

baseline T_2_1:

q: [-0.00020849 -0.00320787 -0.00519355 0.99998135] +- [0.00018672 0.00005059 0.0000352]

t: [0.12004127 0.06906635 0.00308265] +- [0.00003427 0.00003248 0.00010564]

baseline T_3_2:

q: [0.00004475 -0.00272286 0.0002698 0.99999626] +- [0.00027193 0.00004753 0.00003017]

t: [-0.12013732 -0.00005197 0.00155533] +- [0.00003131 0.00002976 0.00009409]

baseline T_4_3:

q: [0.00226052 0.0043163 0.00035922 0.99998807] +- [0.00020671 0.00004672 0.00003104]

t: [0.08895377 0.00614726 0.00285372] +- [0.00003011 0.00002845 0.00009666]

Target configuration

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Type: aprilgrid

Tags:

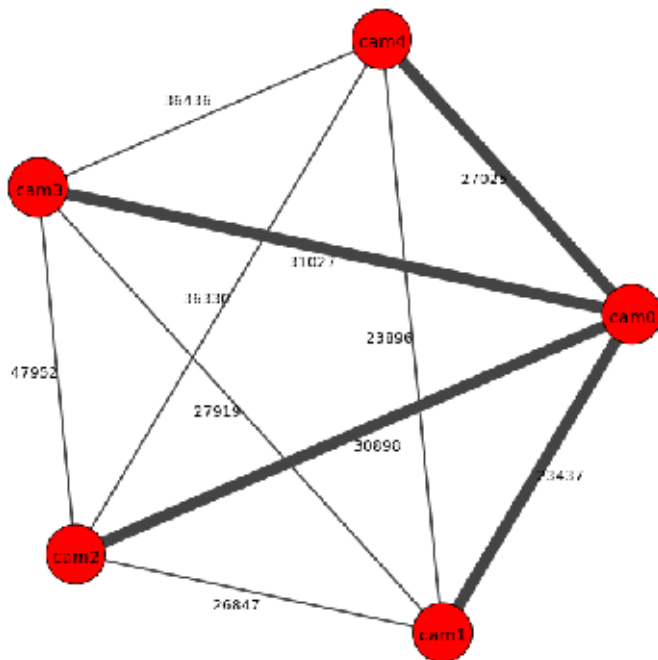
Rows: 5

Cols: 7

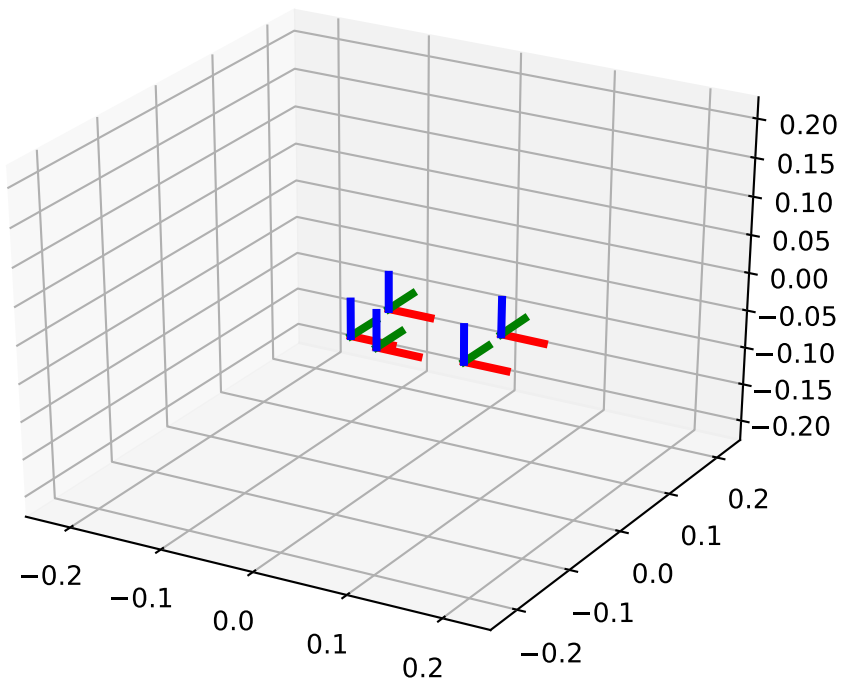
Size: 0.04 [m]

Spacing 0.01 [m]

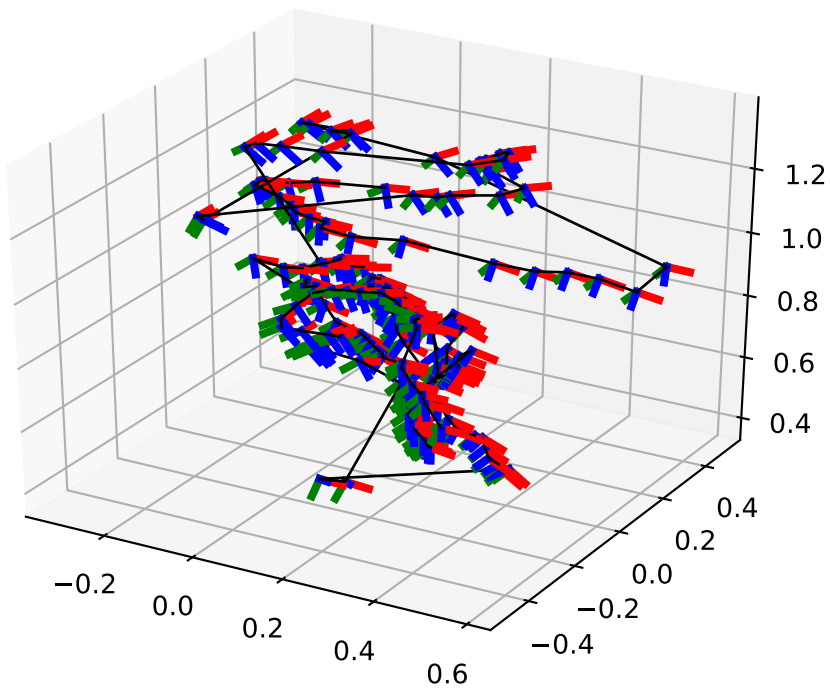
Inter-camera observations graph (edge weight=#mutual obs.)



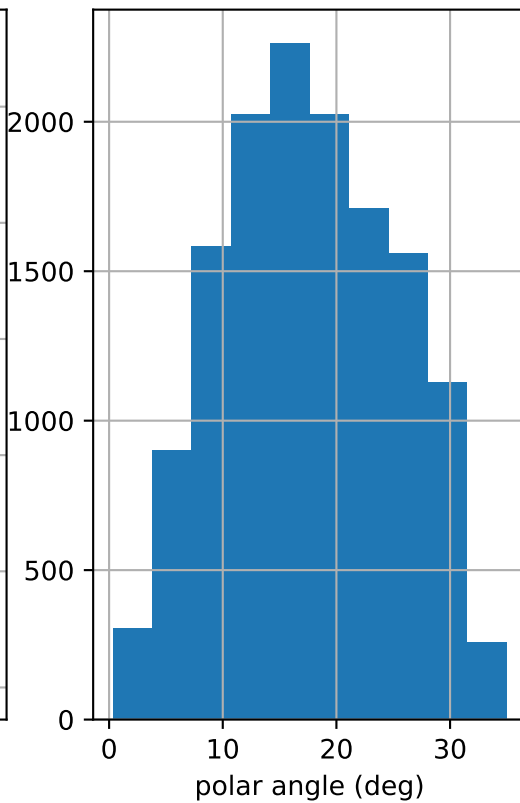
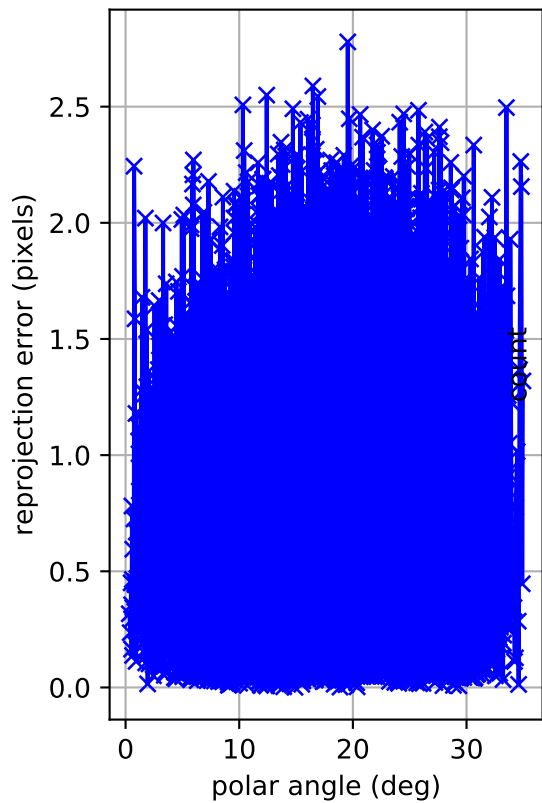
camera system



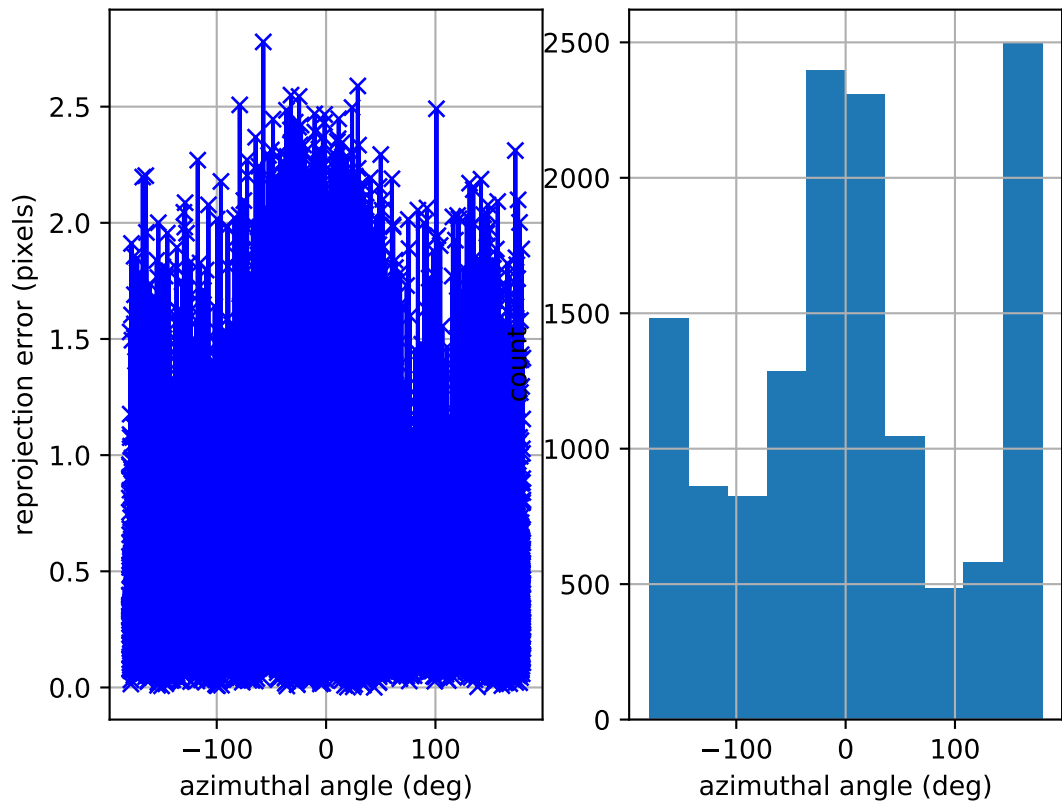
cam0: estimated poses



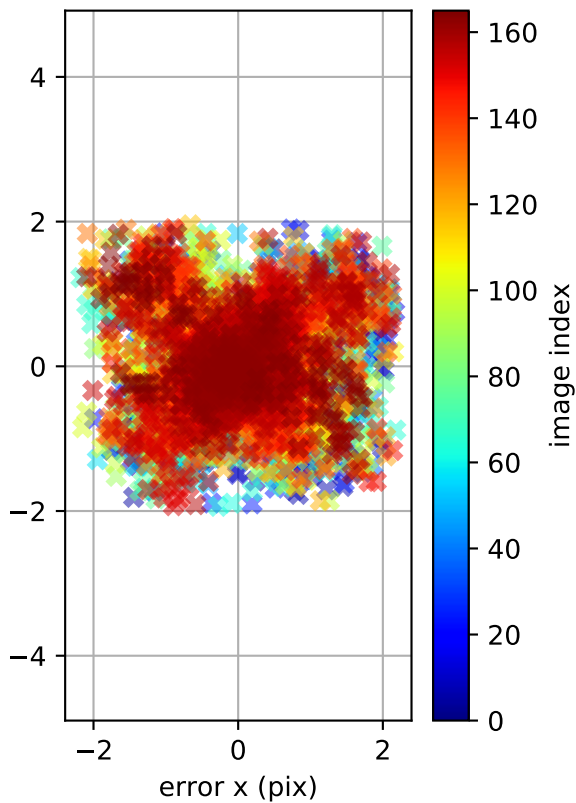
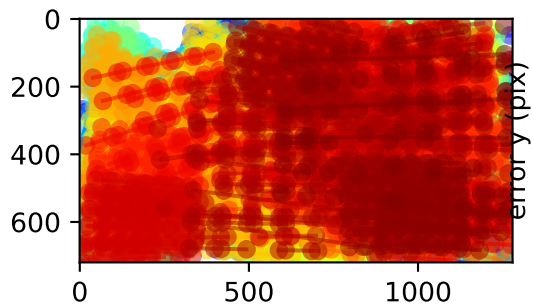
cam0: polar error



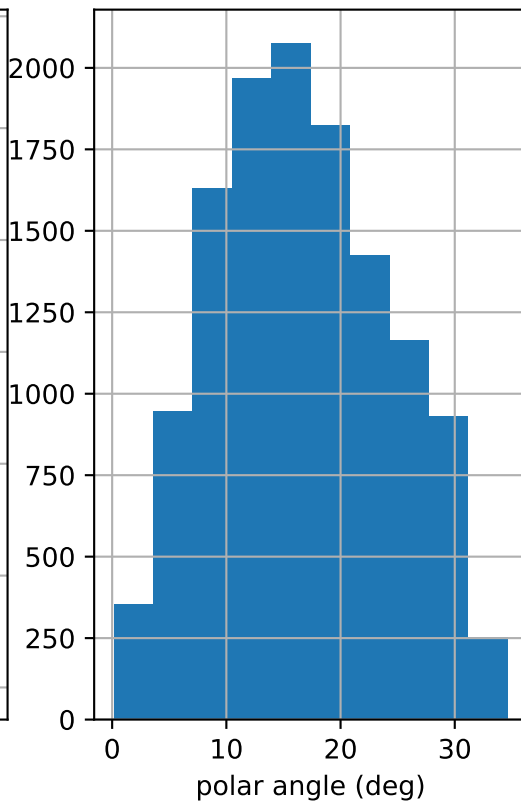
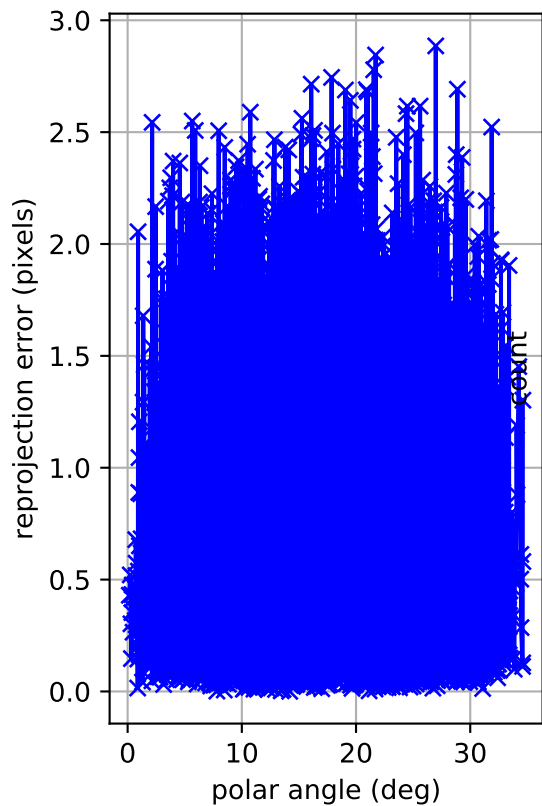
cam0: azimuthal error



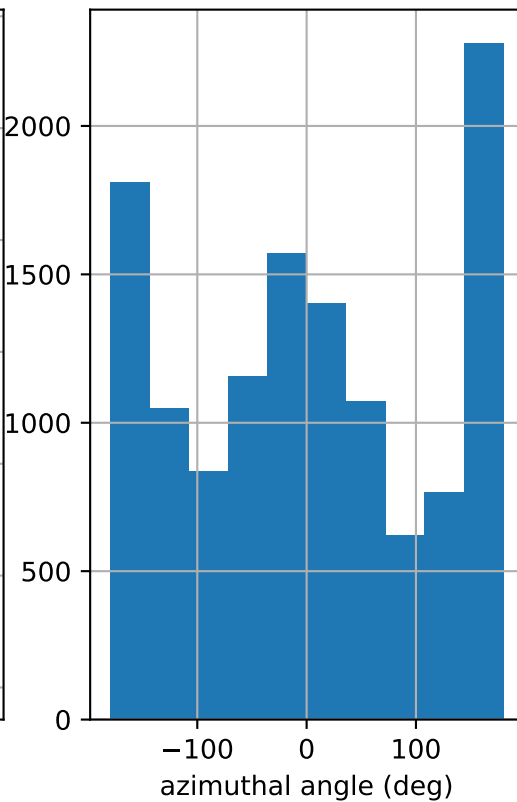
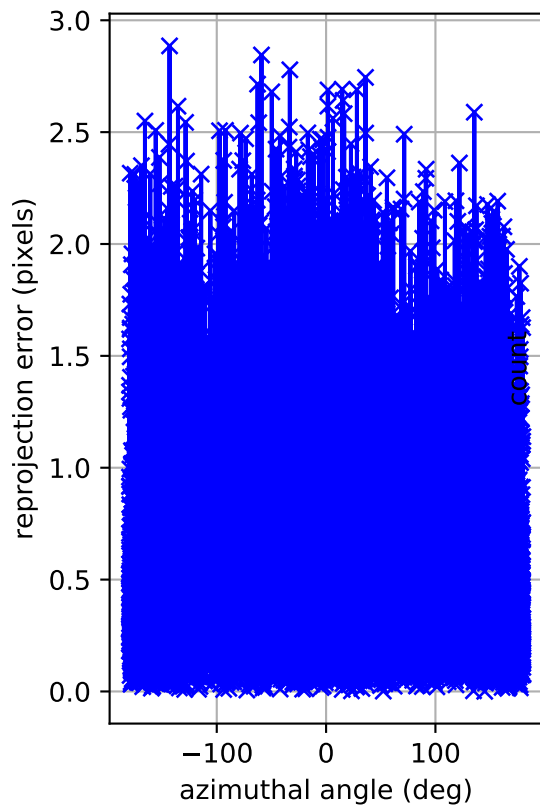
cam0: reprojection errors



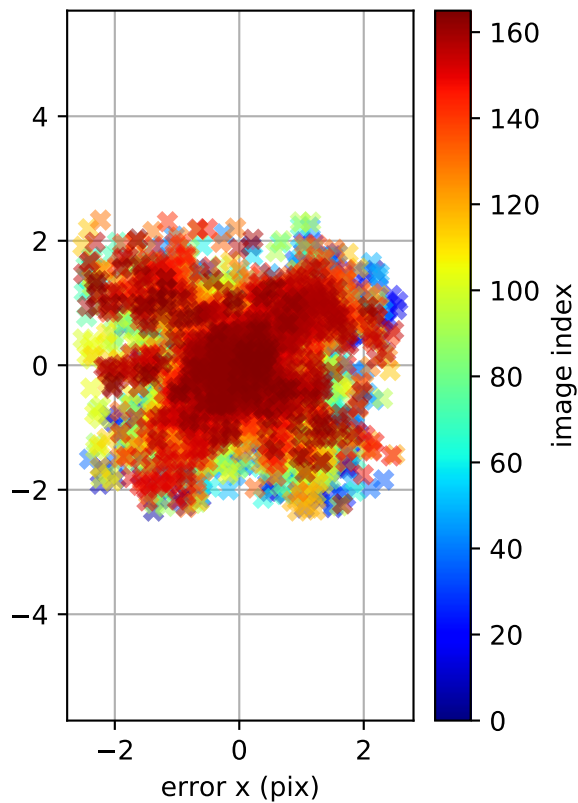
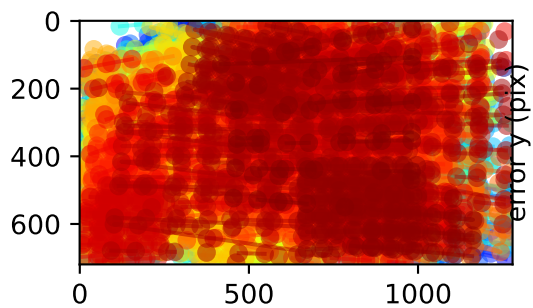
cam1: polar error



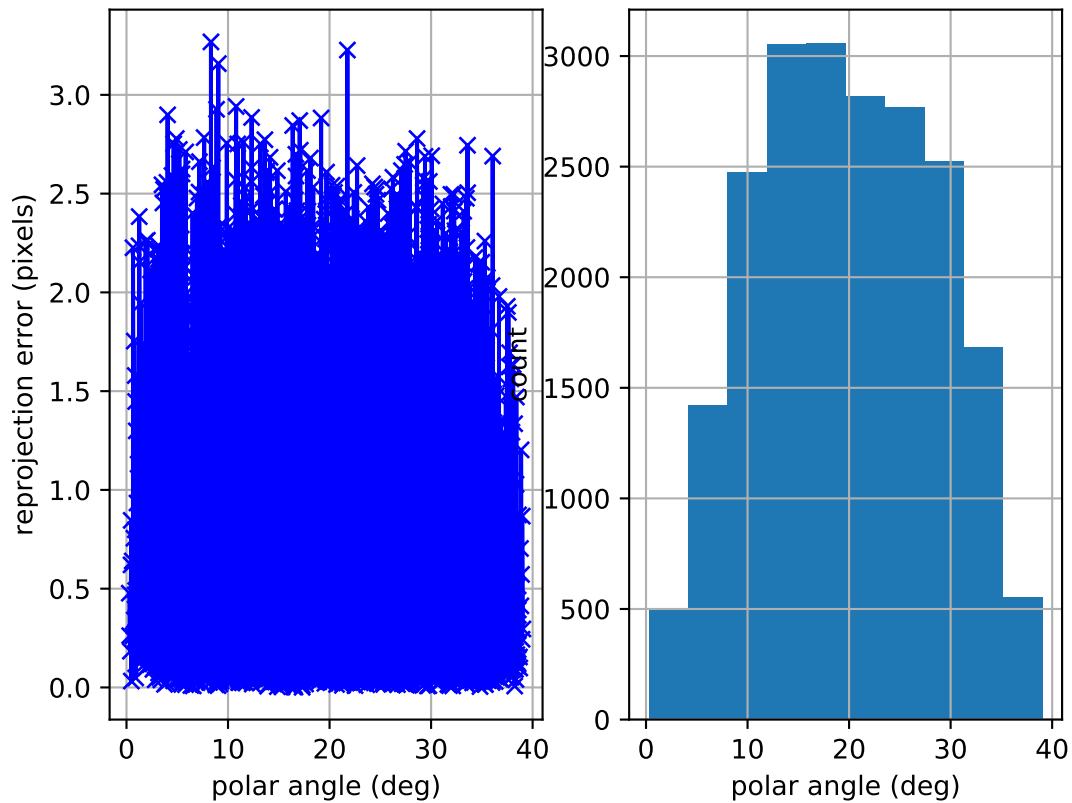
cam1: azimuthal error



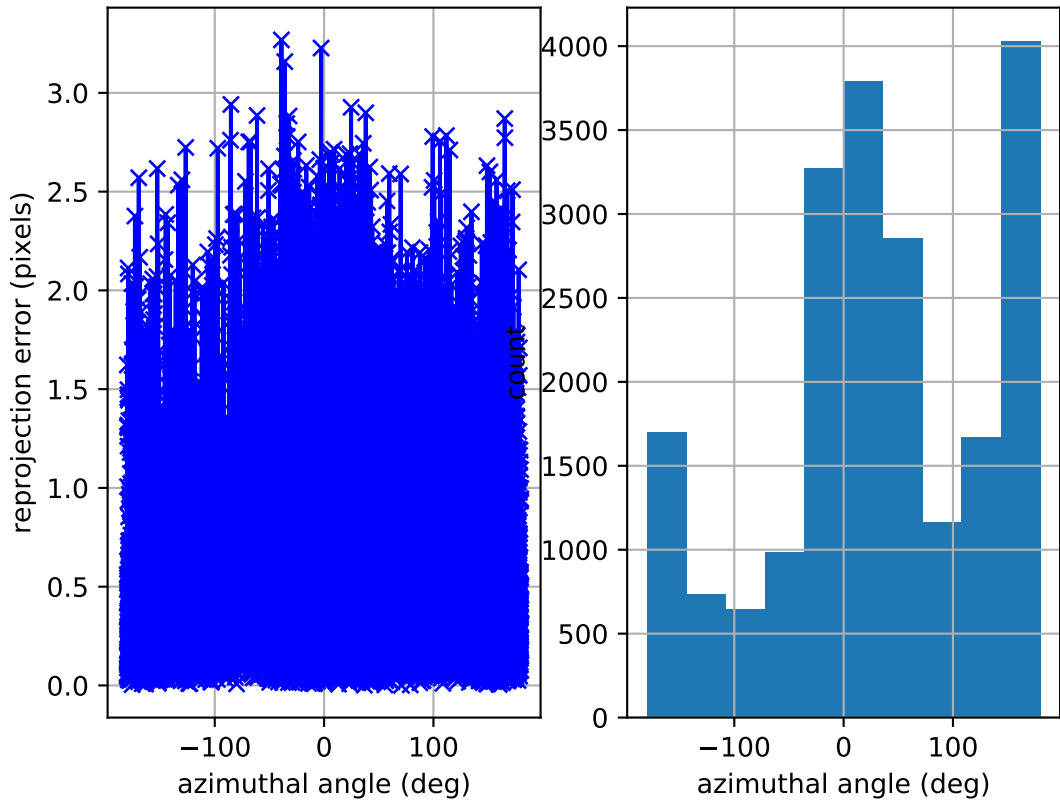
cam1: reprojection errors



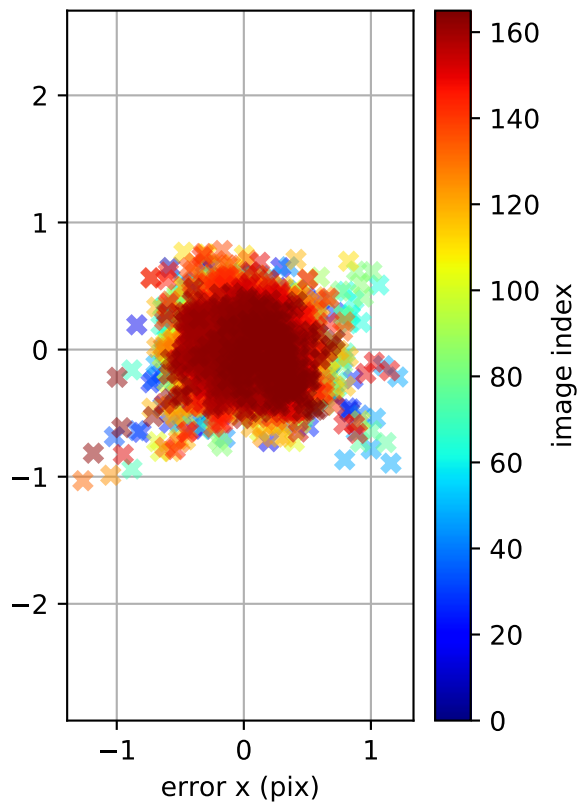
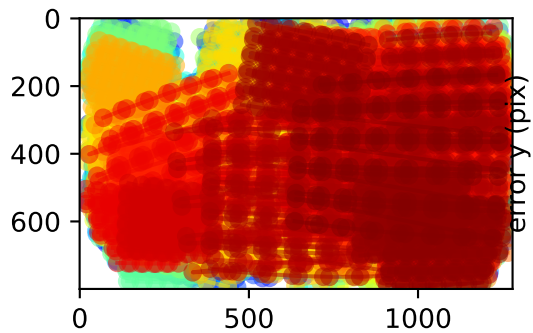
cam2: polar error



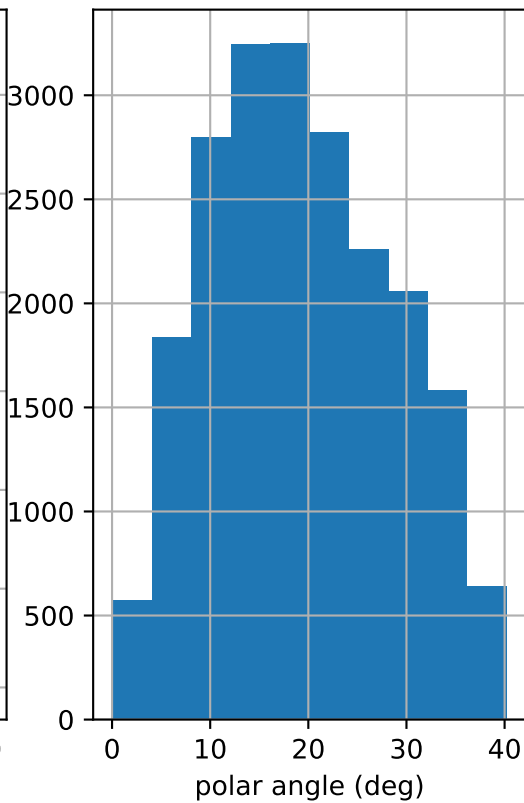
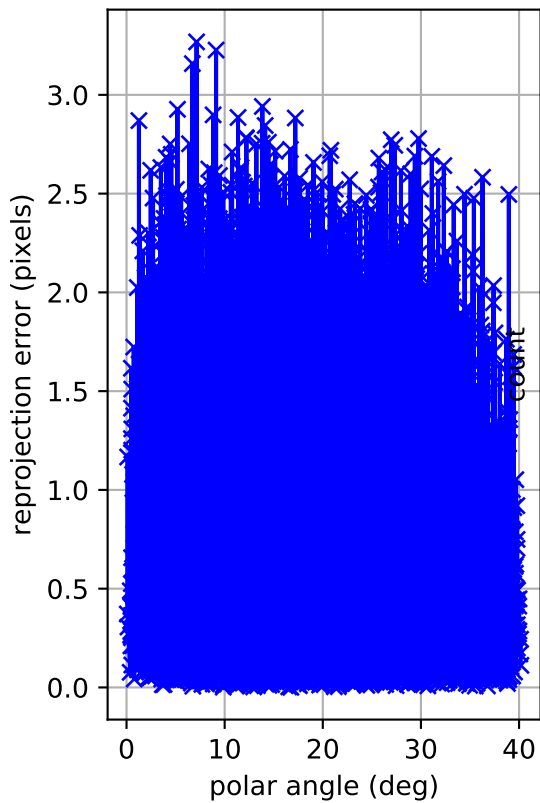
cam2: azimuthal error



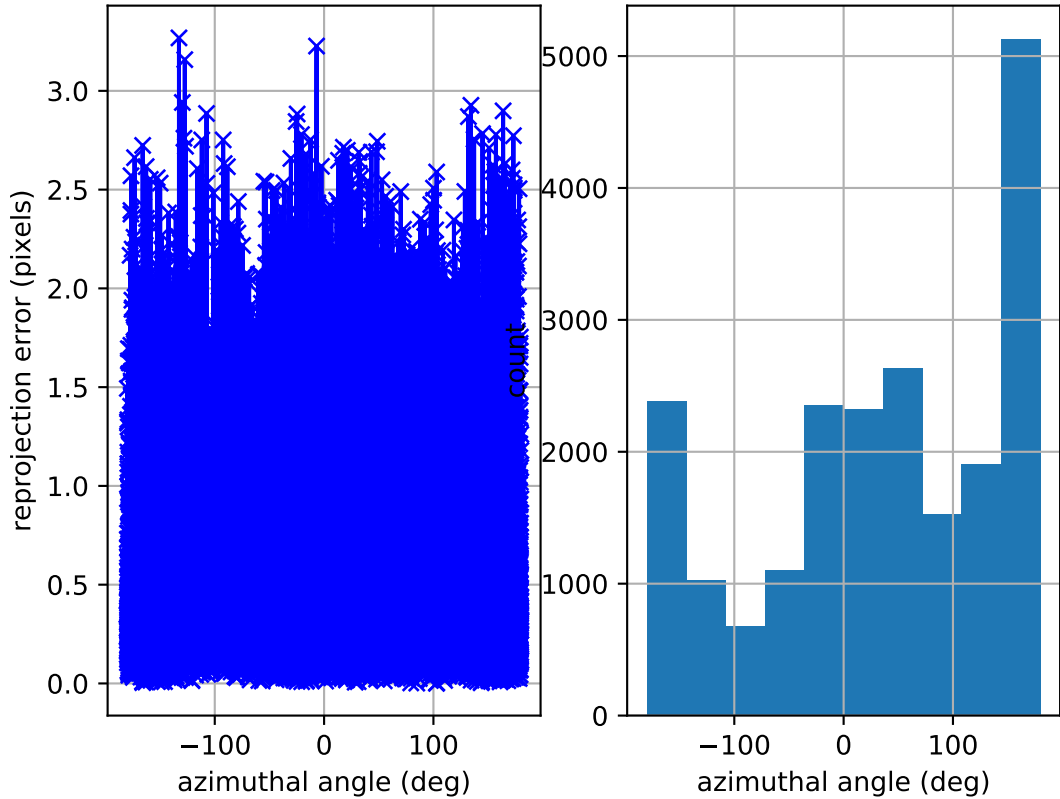
cam2: reprojection errors



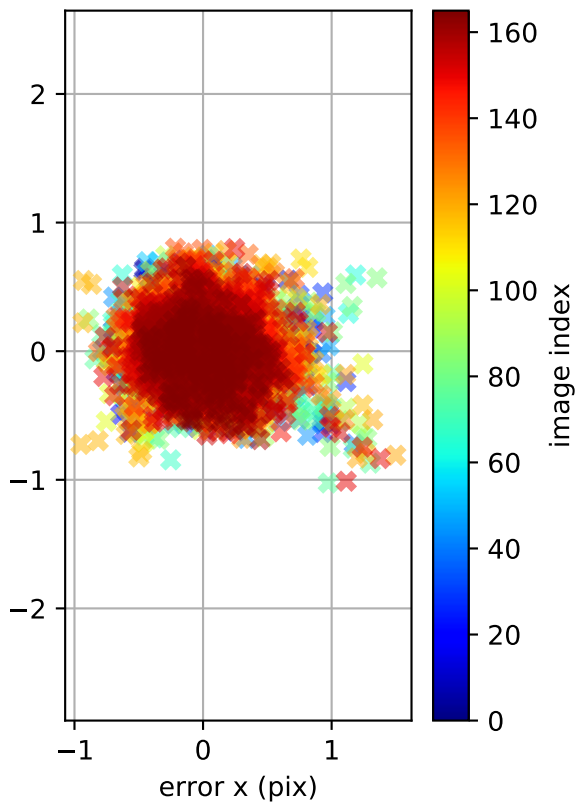
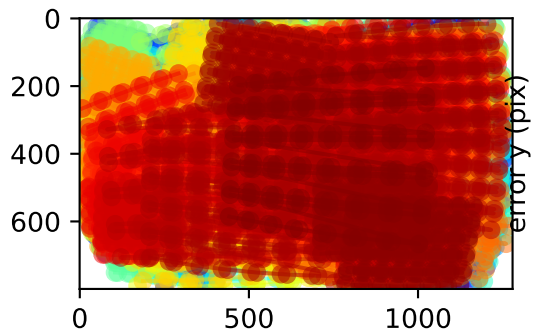
cam3: polar error



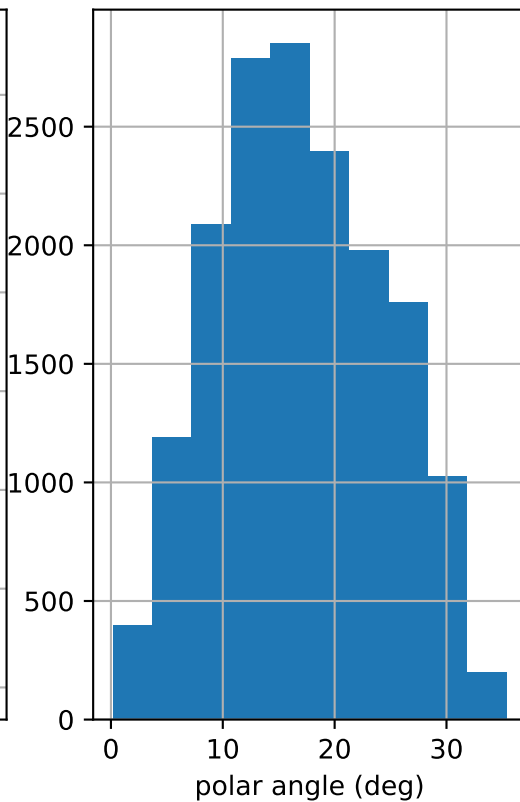
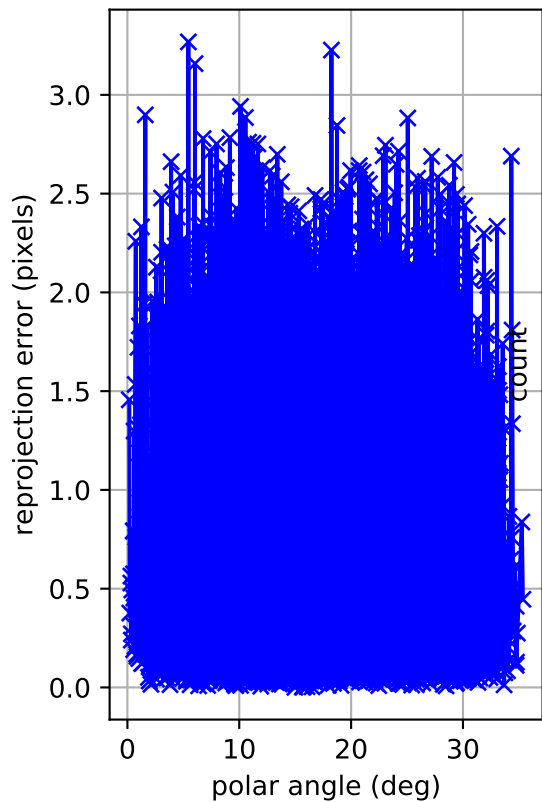
cam3: azimuthal error



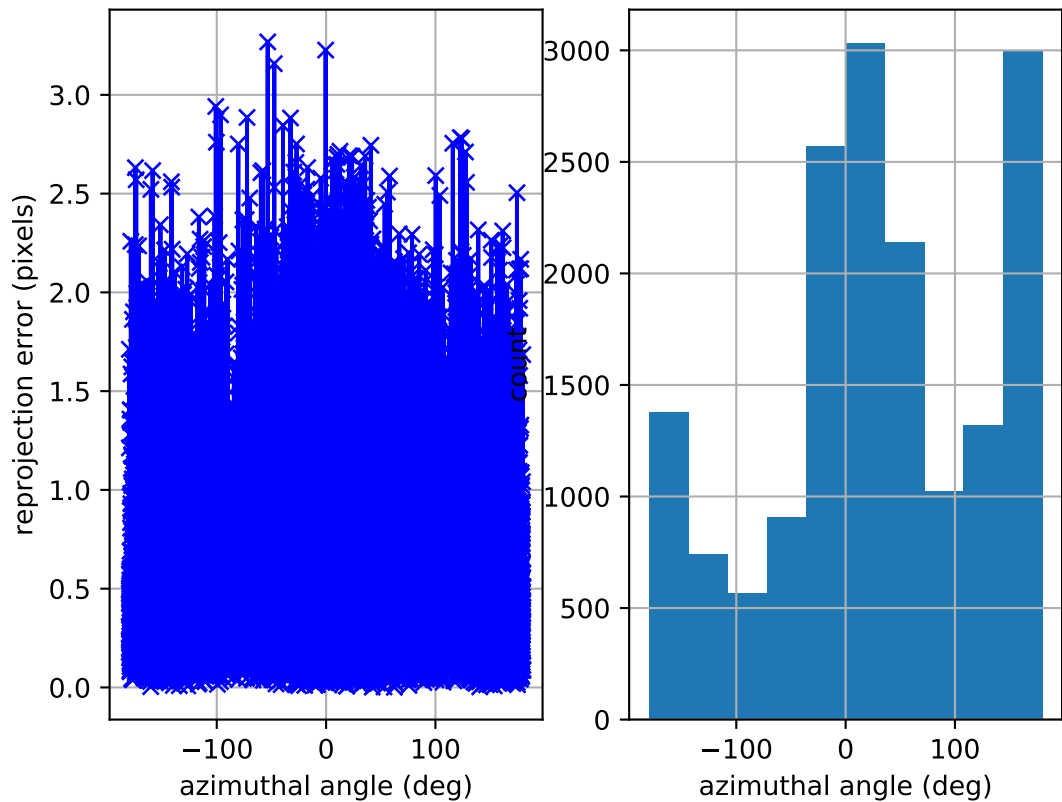
cam3: reprojection errors



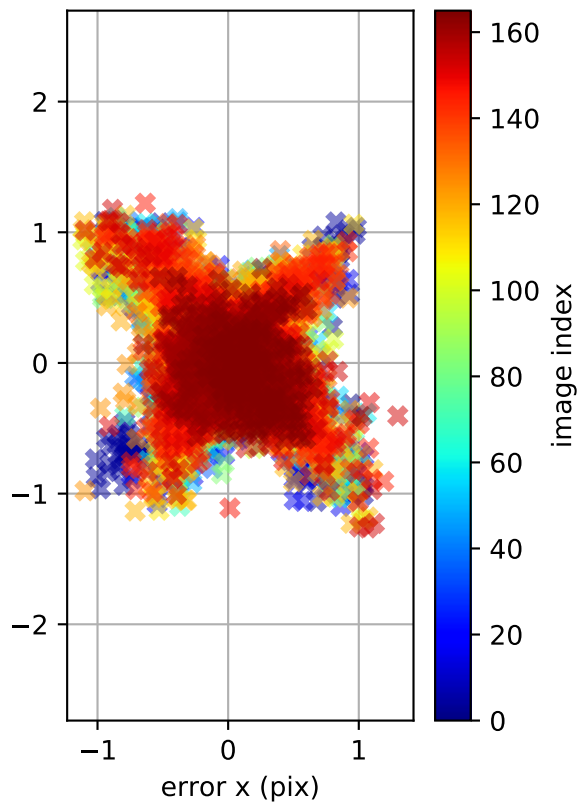
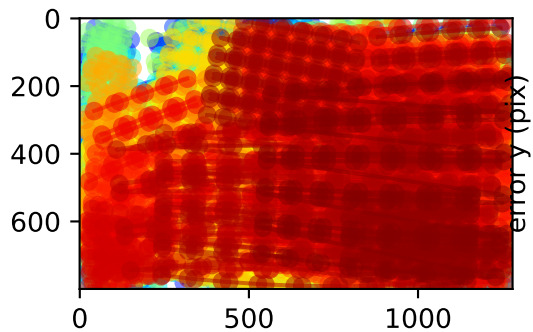
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

