

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04768878 0.08424051 0.00049087 -0.00118628] +- [0.00099614 0.00220871 0.00008046 0.00005666]
projection: [1031.28303548 1031.36293954 635.73771622 366.81925393] +- [0.11461572 0.1127559 0.01148849 0.12301172]

reprojection error: [0.000124, -0.000143] +- [0.418761, 0.374209]

cam1 (/prophesee/right/events):

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

distortion: [-0.04969524 0.07797286 0.00160408 -0.00004523] +- [0.00099222 0.00208355 0.00007479 0.00005787]
projection: [1030.62646968 1030.98305576 636.68872098 368.70448786] +- [0.12718285 0.12042222 0.01431963 0.08690455]

reprojection error: [0.000172, -0.000141] +- [0.495425, 0.443821]

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

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

distortion: [-0.39212253 0.15636268 -0.00029464 0.00054712] +- [0.00049808 0.00086274 0.00005571 0.00003592]
projection: [1057.19198468 1057.71625378 675.0016089 336.00090992] +- [0.09369838 0.09567168 0.03267696 0.20502659]

reprojection error: [0.000239, -0.000165] +- [0.201750, 0.176499]

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

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

distortion: [-0.38840697 0.14703977 -0.0004637 0.00113167] +- [0.000412 0.00059884 0.00005078 0.00003479]
projection: [1051.5658332 1052.55335303 671.66600863 328.89590572] +- [0.0967661 0.09596424 0.02816929 0.20250659]

reprojection error: [0.000336, -0.000207] +- [0.226655, 0.182228]

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

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

distortion: [-0.41474192 0.18541907 0.00023654 -0.00026143] +- [0.00071981 0.00169922 0.00005568 0.00004044]
projection: [1263.07424982 1263.39238608 653.42471609 365.8249043] +- [0.1040701 0.10292772 0.01089345 0.06477345]

reprojection error: [0.000166, -0.000176] +- [0.258150, 0.210257]

baseline T_1_0:

q: [-0.00109081 0.00194504 -0.00032084 0.99999746] +- [0.00007233 0.00004017 0.00004103]

t: [-0.12019248 0.00095277 0.00005218] +- [0.00002713 0.00002387 0.00009071]

baseline T_2_1:

q: [0.00028305 -0.00277765 -0.00512346 0.99998298] +- [0.00024085 0.00005593 0.00003952]

t: [0.12008325 0.06918269 0.00402141] +- [0.00002477 0.00002133 0.00008304]

baseline T_3_2:

q: [0.00017936 -0.0027807 0.00026198 0.99999608] +- [0.00029204 0.00005645 0.00003456]

t: [-0.1199496 -0.00012244 0.0009946] +- [0.00001984 0.0000177 0.00006491]

baseline T_4_3:

q: [0.00261015 0.00551557 0.00038455 0.99998131] +- [0.000231 0.00004437 0.00003472]

t: [0.08881929 0.00623405 0.00319776] +- [0.00001918 0.00001614 0.00006254]

Target configuration

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Type: aprilgrid

Tags:

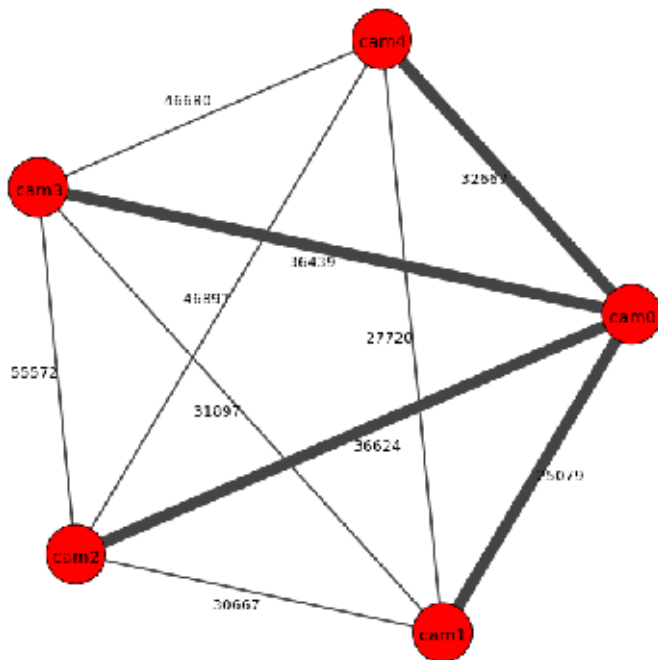
Rows: 5

Cols: 7

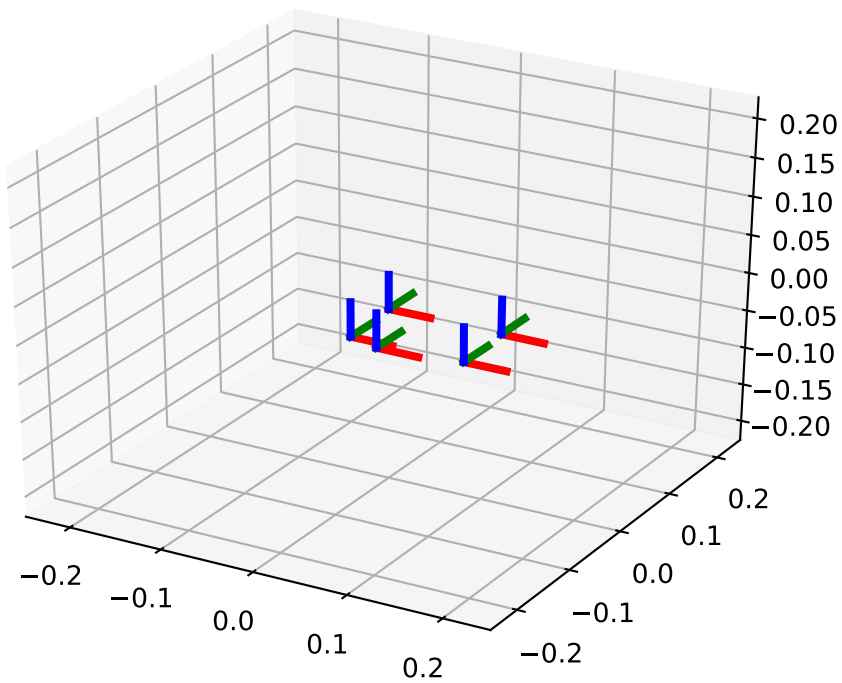
Size: 0.04 [m]

Spacing 0.01 [m]

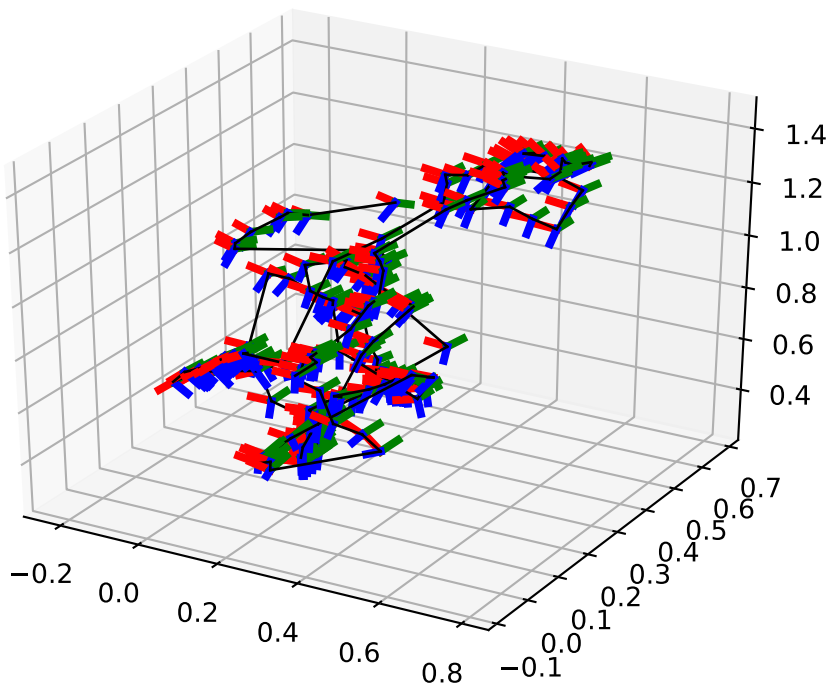
Inter-camera observations graph (edge weight=#mutual obs.)



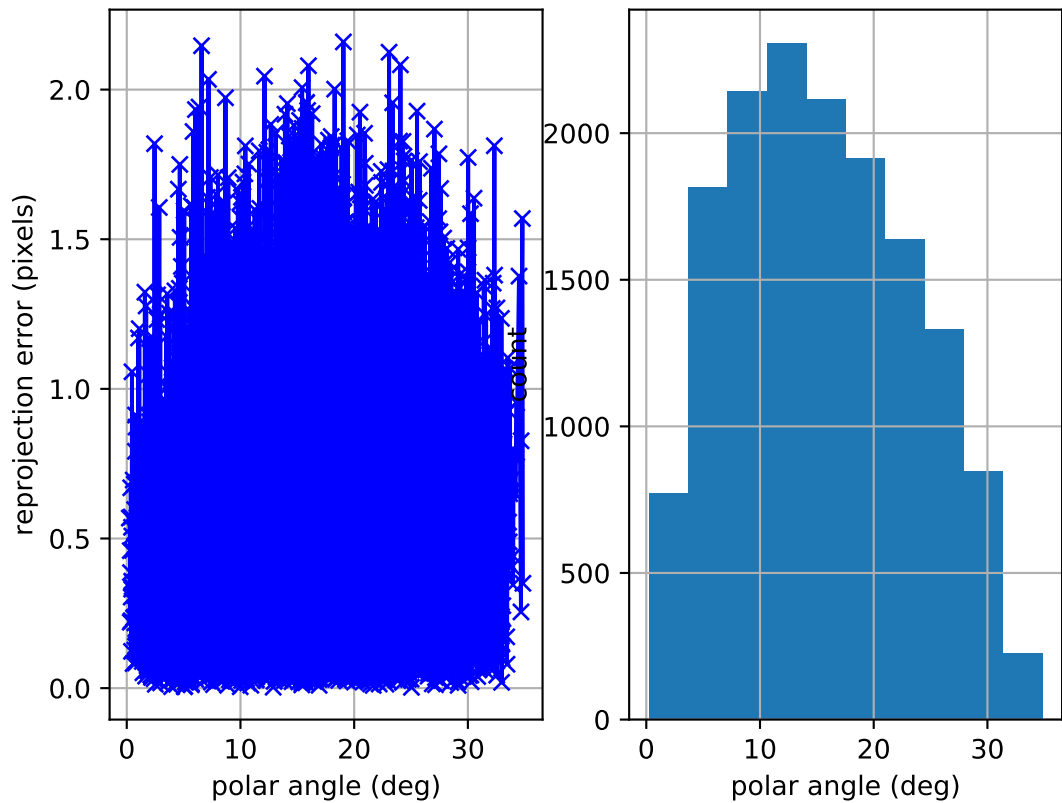
camera system



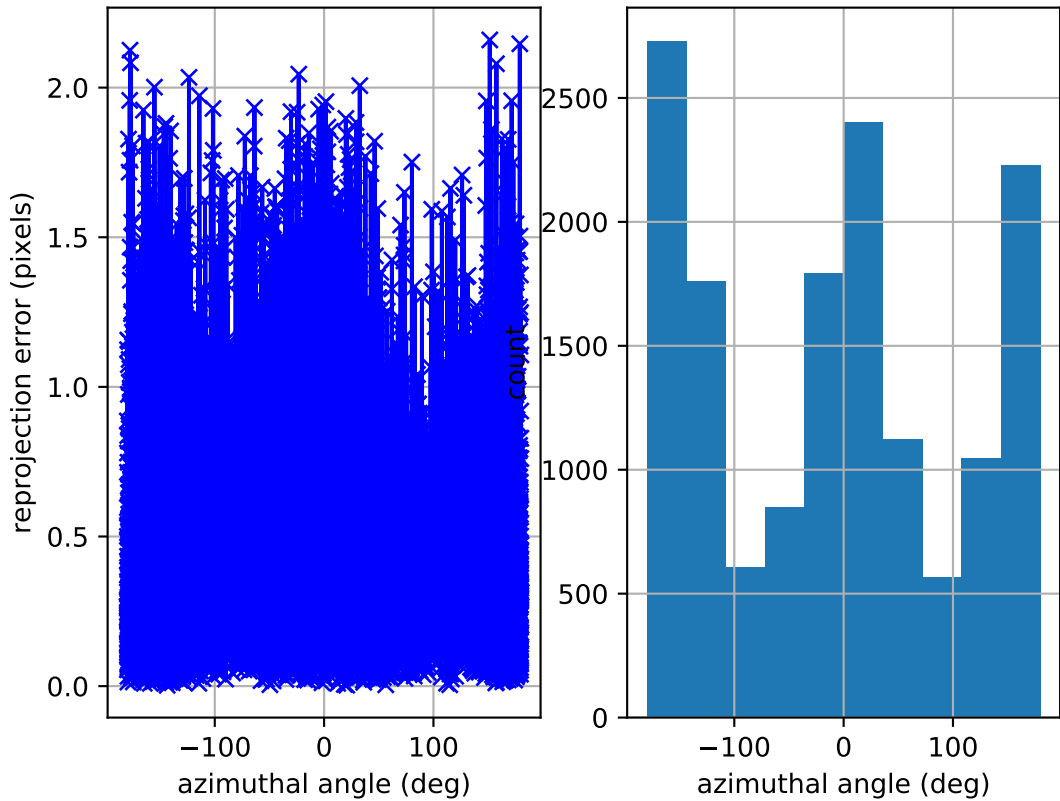
cam0: estimated poses



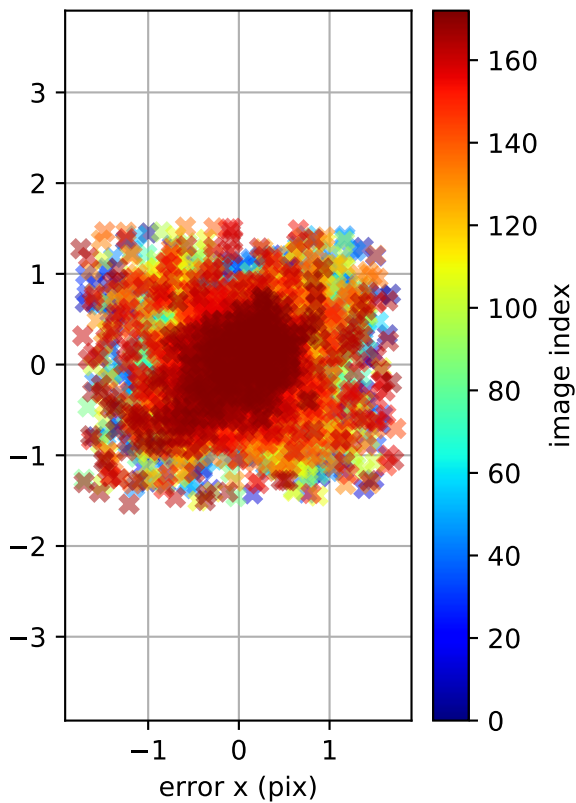
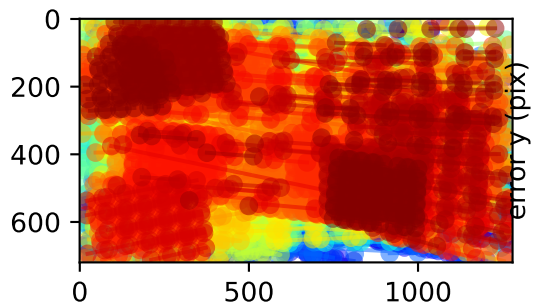
cam0: polar error



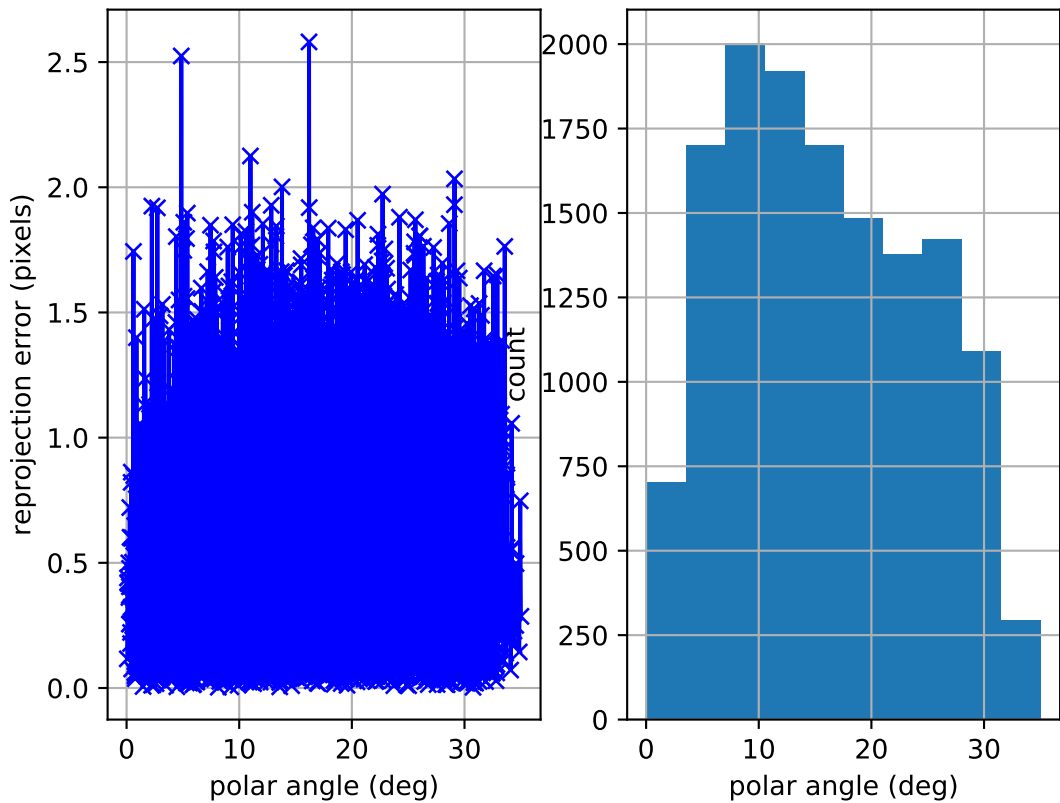
cam0: azimuthal error



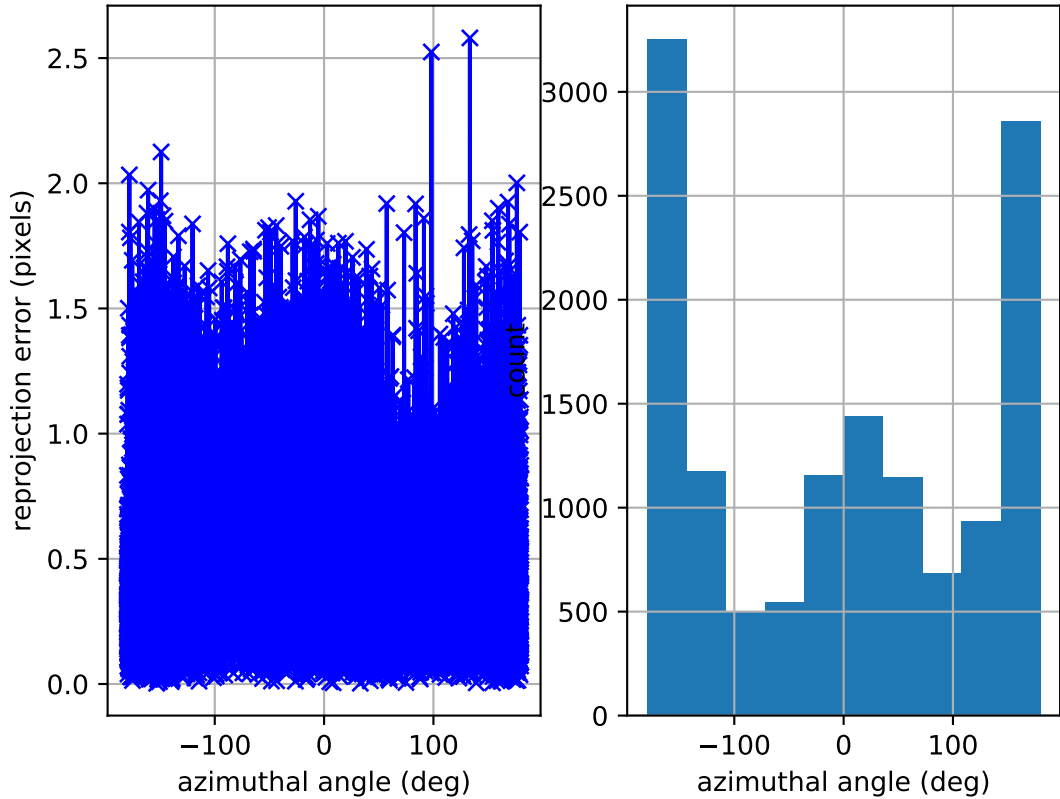
cam0: reprojection errors



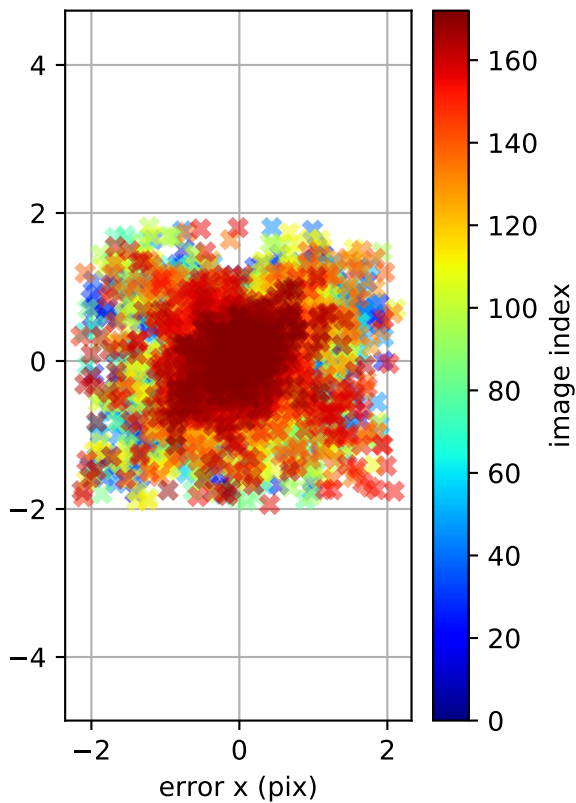
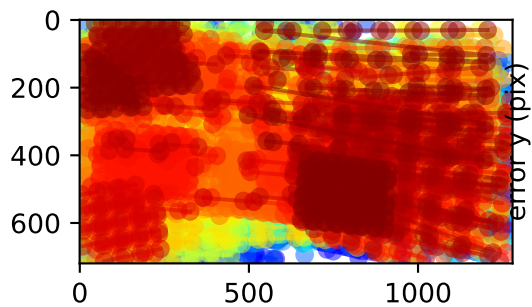
cam1: polar error



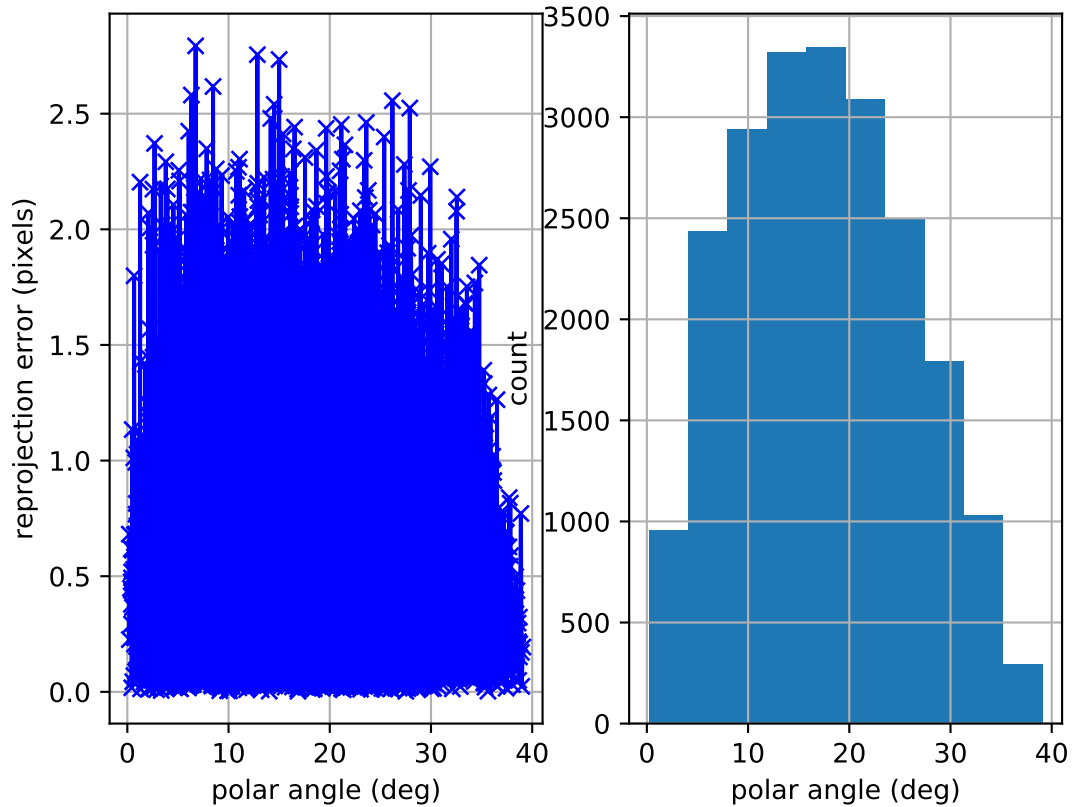
cam1: azimuthal error



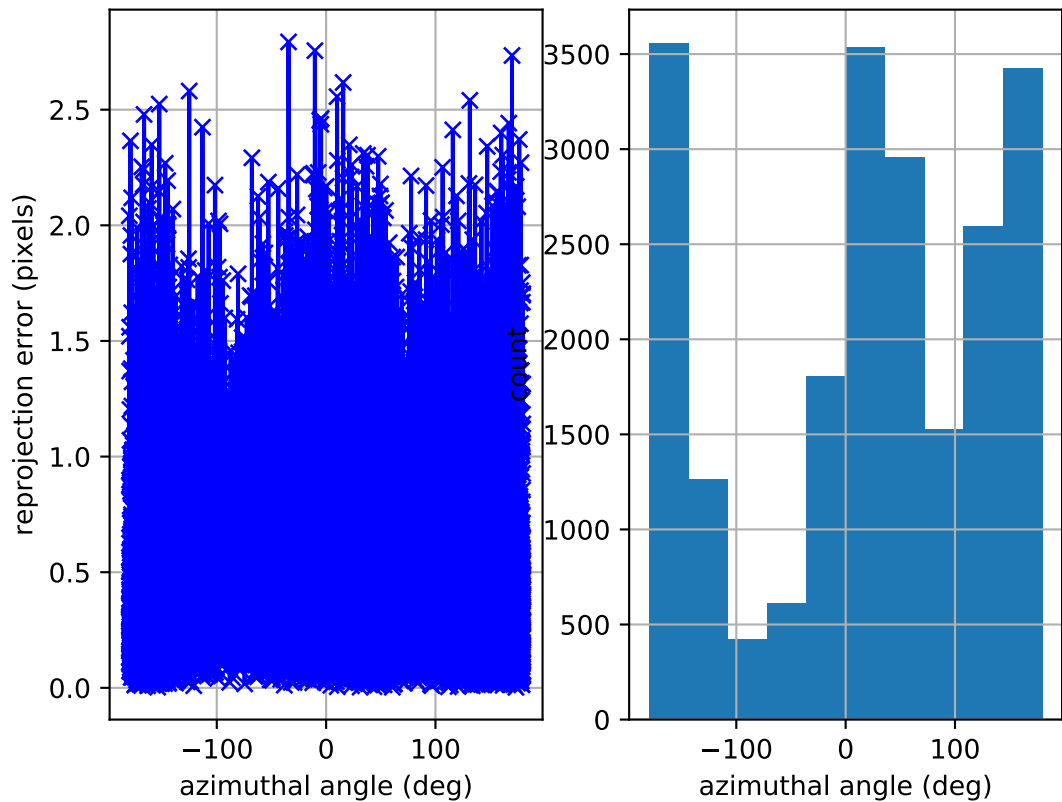
cam1: reprojection errors



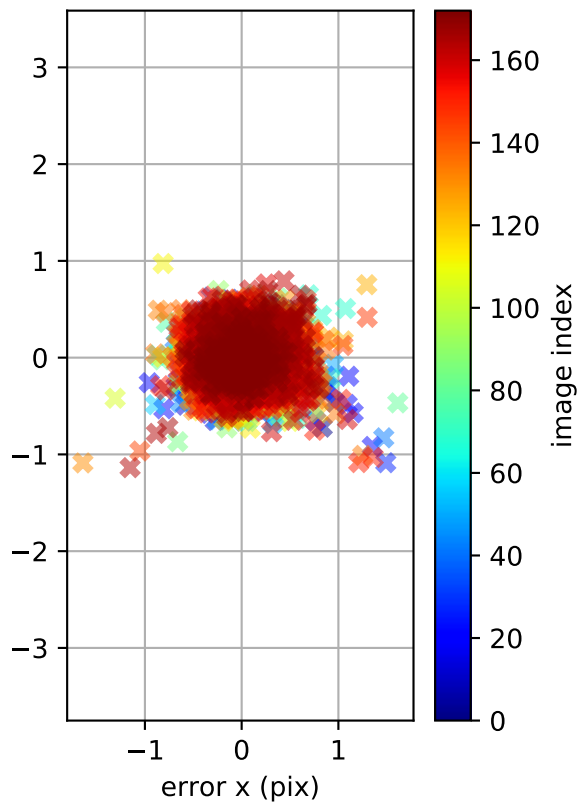
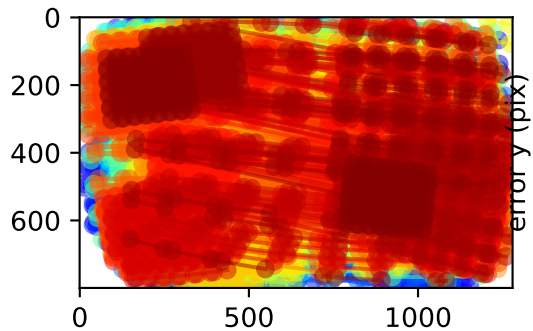
cam2: polar error



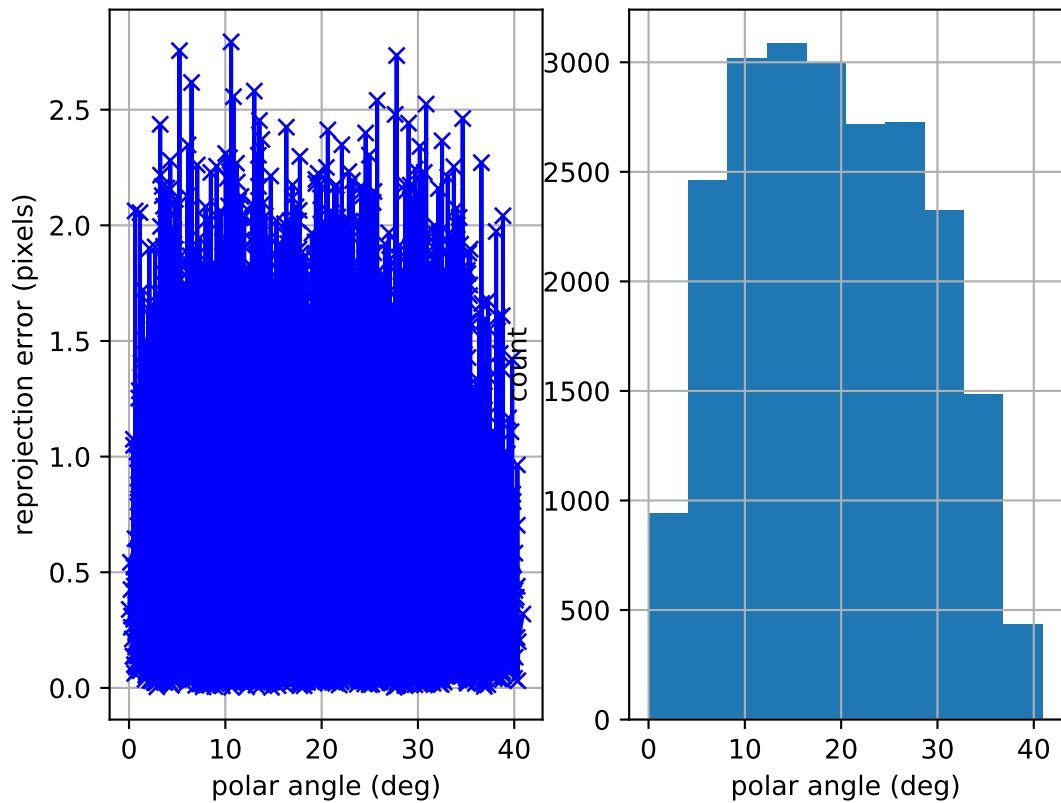
cam2: azimuthal error



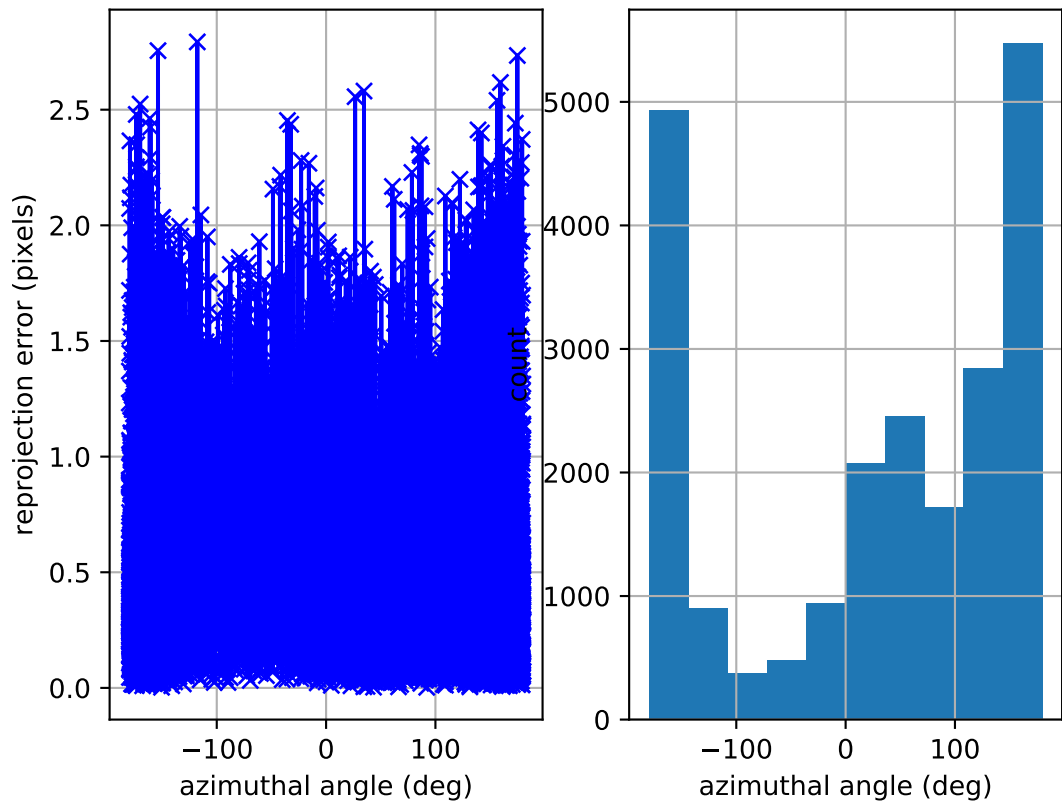
cam2: reprojection errors



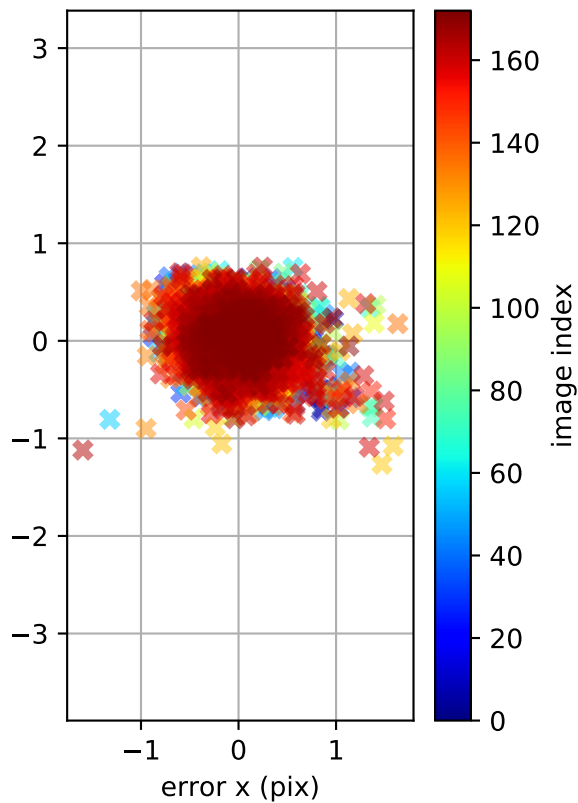
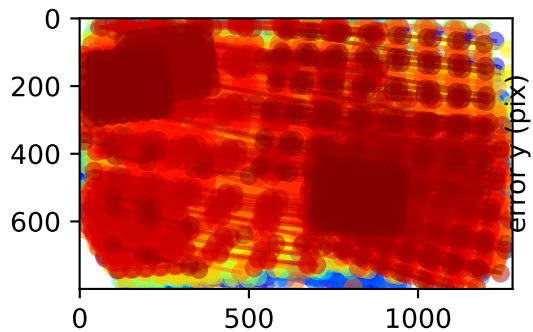
cam3: polar error



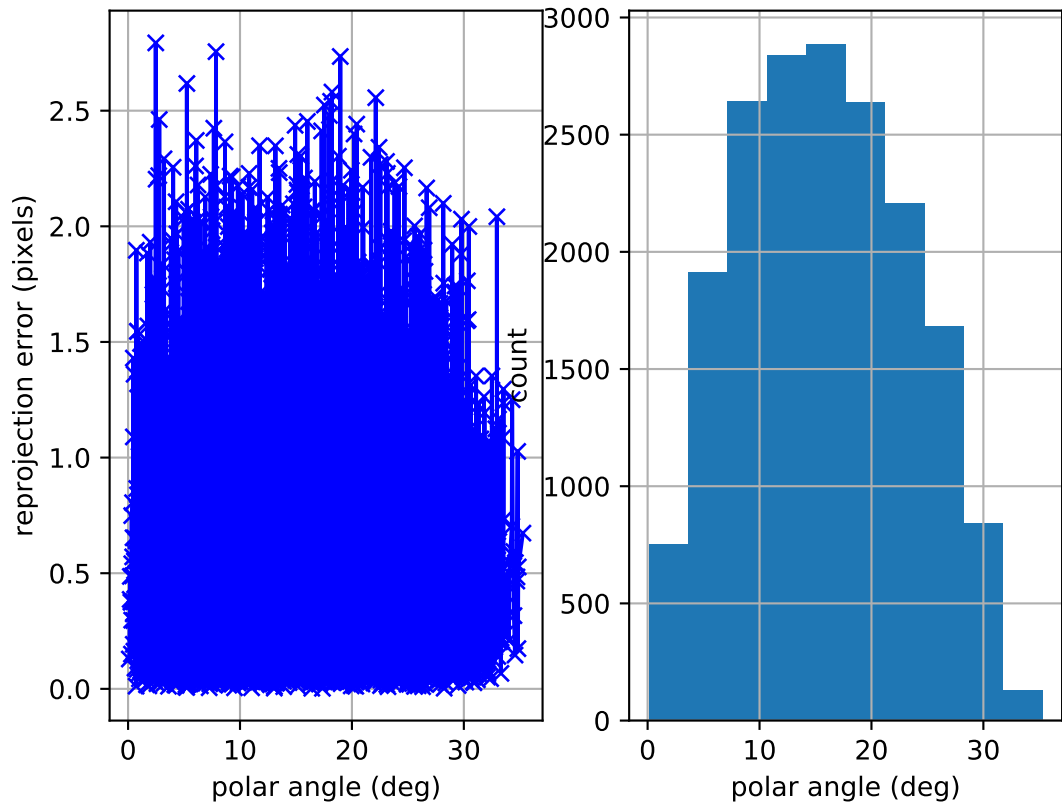
cam3: azimuthal error



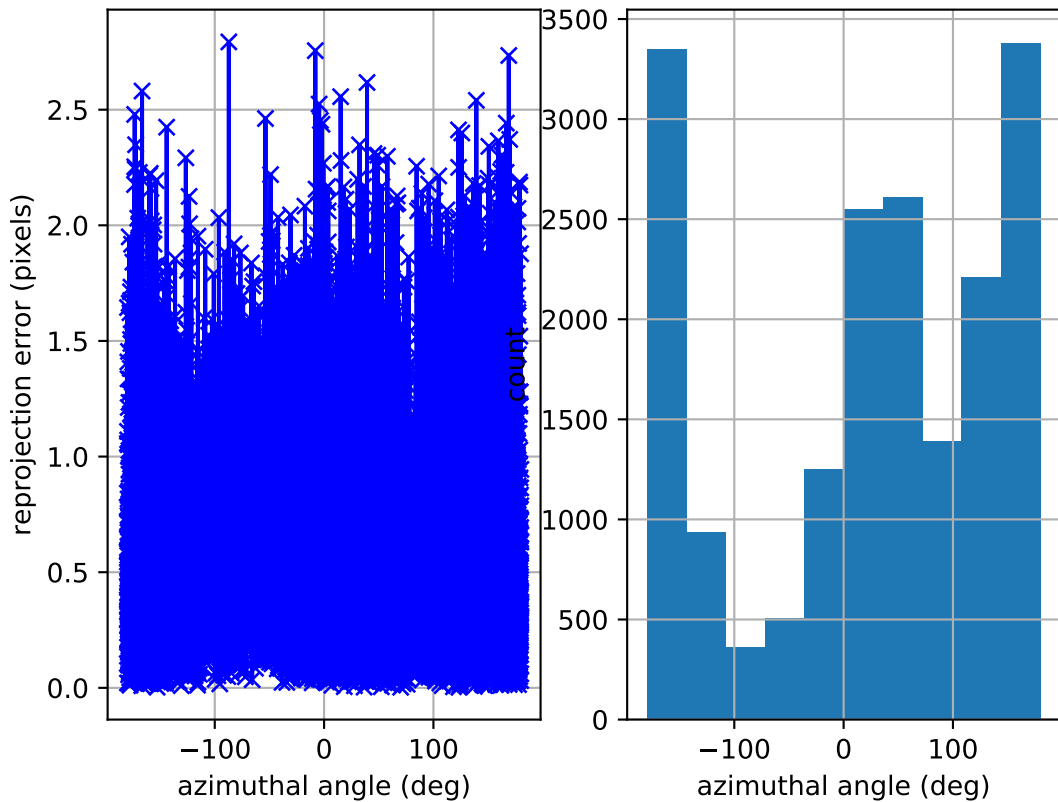
cam3: reprojection errors



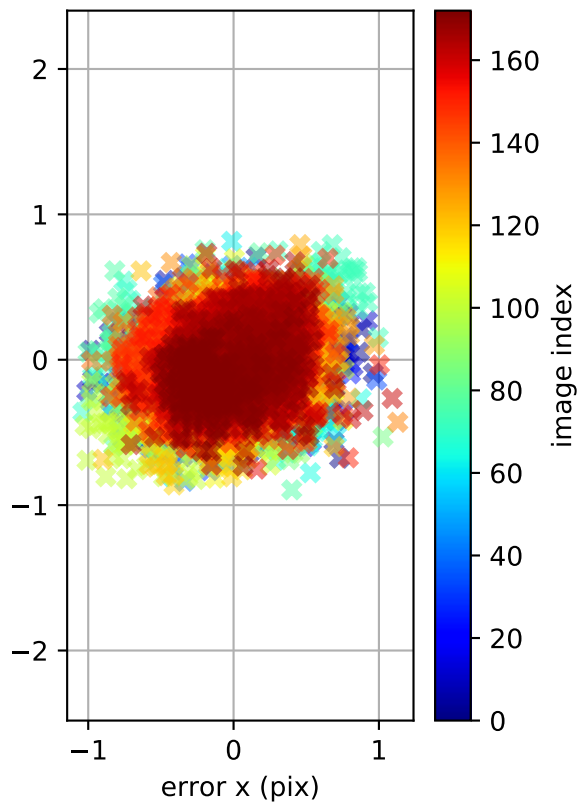
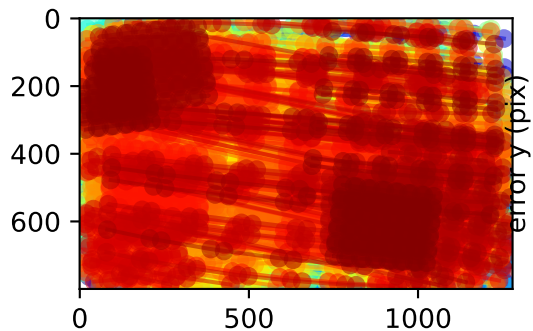
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

